



VCI: C++

Software Version 4

SOFTWARE DESIGN GUIDE

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Important User Information

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1	User Guide	5
1.1	Document History	5
1.2	Trademark Information	5
1.3	Conventions.....	5
1.4	Glossary	6
2	System Overview.....	7
2.1	Features and Components	7
2.2	Programming Examples.....	8
2.3	Using the VCI Headers.....	8
3	Device Management and Device Access.....	9
3.1	Listing Available Devices.....	10
3.2	Accessing Individual Devices	11
4	Communication Components	12
4.1	First In/First Out Memory (FIFO)	13
4.1.1	Functionality of the Receiving FIFO	16
4.1.2	Functionality of the Transmitting FIFO	18
5	Accessing the Bus Controller	20
5.1	BAL.....	20
5.2	CAN Controller	22
5.2.1	Socket Interface.....	22
5.2.2	Message Channels.....	23
5.2.3	Control Unit	33
5.2.4	Message Filter.....	42
5.2.5	Cyclic Transmitting List.....	46
5.3	LIN-Controller.....	49
5.3.1	Socket Interface.....	49
5.3.2	Message Monitors	50
5.3.3	Control Unit	53

6	Error Messages	56
7	Interface Description.....	57
7.1	Exported Functions.....	57
7.1.1	VciInitialize.....	57
7.1.2	VciFormatError.....	57
7.1.3	VciGetVersion	58
7.1.4	VciCreateLuid.....	58
7.1.5	VciLuidToChar	59
7.1.6	VciCharToLuid	59
7.1.7	VciGuidToChar	60
7.1.8	VciCharToGuid	60
7.1.9	VciGetDeviceManager	61
7.1.10	VciQueryDeviceByHwid	61
7.1.11	VciQueryDeviceByClass	62
7.1.12	VciCreateFifo	62
7.1.13	VciAccessFifo	63
7.2	Interface IUnknown.....	64
7.2.1	QueryInterface	64
7.2.2	AddRef.....	64
7.2.3	Release	65
7.3	Interfaces of the Device Management	66
7.3.1	IVciDeviceManager	66
7.3.2	IVciEnumDevice	67
7.3.3	IVciDevice	69
7.4	Interfaces of the Communication Components.....	71
7.4.1	Interfaces for FIFOs.....	71
7.5	BAL Specific Interfaces	84
7.5.1	IBalObject	84
7.6	CAN Specific Interfaces	86
7.6.1	ICanSocket	86
7.6.2	ICanSocket2.....	88
7.6.3	ICanControl	90
7.6.4	ICanControl2.....	95
7.6.5	ICanChannel	101
7.6.6	ICanChannel2.....	104
7.6.7	ICanScheduler	111
7.6.8	ICanScheduler2.....	115
7.7	LIN Specific Interface	119
7.7.1	ILinSocket	119
7.7.2	ILinControl	121
7.7.3	ILinMonitor	124

8 Data Structures.....	127
8.1 VCI Specific Data Types	127
8.1.1 VCIID.....	127
8.1.2 VCIVERSIONINFO.....	127
8.1.3 VCIDEVICEINFO.....	128
8.1.4 VCIDEVICECAPS	129
8.2 BAL Specific Data Types.....	129
8.2.1 BALFEATURES	129
8.2.2 BALSOCKETINFO	130
8.3 CAN Specific Data Types.....	130
8.3.1 CANCAPABILITIES	130
8.3.2 CANCAPABILITIES2.....	132
8.3.3 CANBTRTABLE.....	134
8.3.4 CANBTP.....	135
8.3.5 CANBTPTABLE	136
8.3.6 CANINITLINE	137
8.3.7 CANINITLINE2	138
8.3.8 CANLINESTATUS	139
8.3.9 CANLINESTATUS2.....	140
8.3.10 CANCHANSTATUS.....	141
8.3.11 CANCHANSTATUS2	141
8.3.12 CANSCHEDULERSTATUS	142
8.3.13 CANSCHEDULERSTATUS2.....	142
8.3.14 CANMSGINFO	143
8.3.15 CANMSG	146
8.3.16 CANMSG2.....	146
8.3.17 CANCYCLICTXMSG	147
8.3.18 CANCYCLICTXMSG2.....	148
8.4 LIN Specific Data Types	149
8.4.1 LINCAPABILITIES	149
8.4.2 LININITLINE	149
8.4.3 LINLINESTATUS.....	150
8.4.4 LINMONITORSTATUS.....	150
8.4.5 LINMSGINFO	151
8.4.6 LINMSG.....	153

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1 User Guide

Please read the manual carefully. Make sure you fully understand the manual before using the product.

1.1 Document History

Version	Date	Description
1.0	June 2016	First version
1.1	January 2017	Minor corrections
1.2	January 2018	Added path to examples, adjusted system overview
1.3	September 2018	Minor corrections, added instructions for including defines
1.4	May 2019	Layout changes

1.2 Trademark Information

Ixxat® is a registered trademark of HMS Industrial Networks. All other trademarks mentioned in this document are the property of their respective holders.

1.3 Conventions

Instructions and results are structured as follows:

- ▶ instruction 1
- ▶ instruction 2
 - result 1
 - result 2

Lists are structured as follows:

- item 1
- item 2

Bold typeface indicates interactive parts such as connectors and switches on the hardware, or menus and buttons in a graphical user interface.

This font is used to indicate program code and other kinds of data input/output such as configuration scripts.

This is a cross-reference within this document: [Conventions, p. 5](#)

This is an external link (URL): www.hms-networks.com



This is additional information which may facilitate installation and/or operation.



This instruction must be followed to avoid a risk of reduced functionality and/or damage to the equipment, or to avoid a network security risk.

1.4 Glossary

Abbreviations

BAL	Bus Access Layer
CAN	Controller Area Network
FIFO	First In/First Out Memory
GUID	Globally unique ID
LIN	Local Interconnect Network
VCI	Virtual Communication Interface
VCIID	VCI specific unique ID
VCI server	VCI system service

2 System Overview

The VCI (Virtual Communication Interface) is a system extension, that provides common access to different devices by HMS Industrial Networks for applications. In this guide the C++ user mode programming interface VCIAPI.DLL is described.

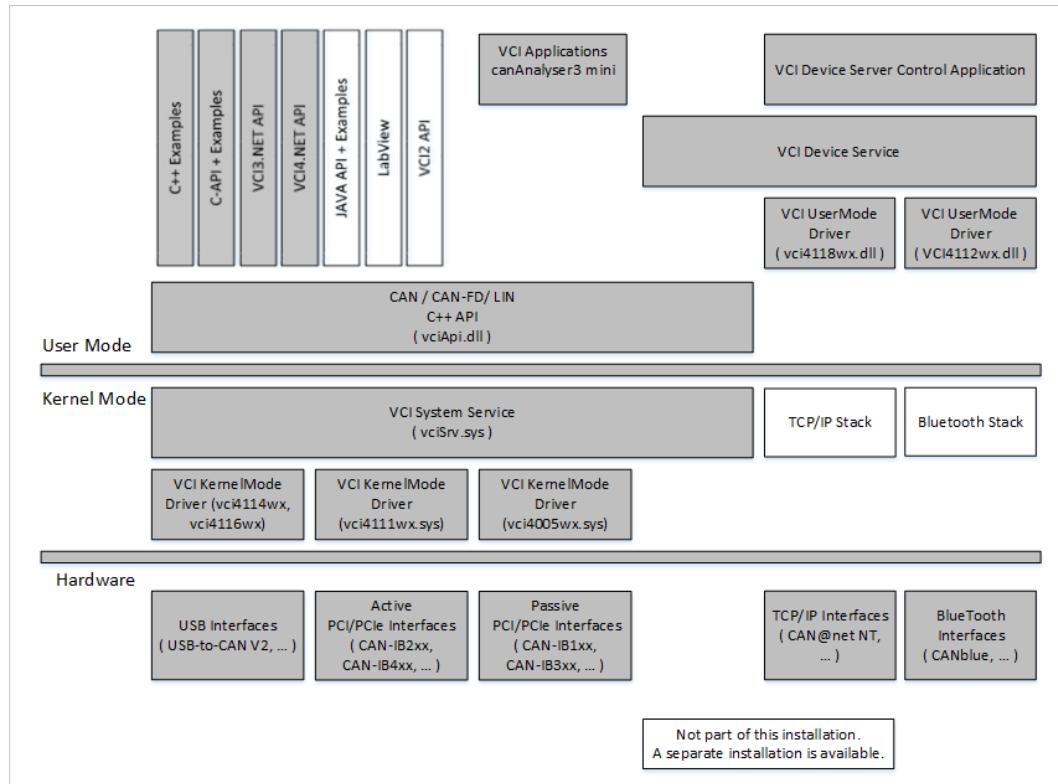


Fig. 1 System structure and components

2.1 Features and Components

The programming interfaces connect the VCI server and the application programs using predefined components, interfaces and functions.

The user mode programming interface (VCIAPI.DLL) is the basis for all superior programming interfaces and applications. The provided components implement the interface `IUnknown`, that is defined by MS-COM. The server functionality that is also specified in MS-COM is not implemented, resp. not supported. The components do not have a COM conform fabric or automation interface, i. e. VCI specific components are not created with `IClassFactory` and do not have an `IDispatch` interface compatible to automation. They can not be used by script or .NET languages.

Regarding multi threading, simultaneous access to particular components from several threads is possible. Every thread has to open an own instance of the desired component resp. interface. The individual functions of an interface must not be called by different threads, because the implementation is not thread safe due to performance reasons. Interfaces, that have an own locking mechanism are an exception to this rule. This locking mechanism is for example provided by the interfaces `IFifoReader` and `IFifoWriter` with the functions `Lock()` and `Unlock()`.

The components do not have to be assigned to an apartment, as usual in COM. If the VCIAPI is used exclusively, without any other COM components the particular threads of an application do not have to be assigned to an apartment nor create an apartment and therefore do not have to call the function `CoInitialize()`.

2.2 Programming Examples

With installing the VCI driver, programming examples are automatically installed in *c:\Users\Public\Documents\HMS\Ixxat VCI 4.0\Samples\SDK*.



If developing own projects, make sure to integrate the file *\common\uuids.c* into the project to correctly initialize the GUIDs (see [Using the VCI Headers, p. 8](#)).

2.3 Using the VCI Headers

The headers of the GUIDs that are used in a project must be included to define the VCI specific GUIDs and the define INITGUID must be set. If the definitions are not included, the error *LNK2001* is returned when compiling the project.

- ▶ In own projects include the c-file *uuids.c* (from the demo).
 - GUIDs of the VCI V4 SDK are initialized.
 - Class IDs are defined.
- ▶ Make sure, that the GUIDs are initialized only once.

3 Device Management and Device Access

The device management provides listing of and access to devices logged into the VCI server.

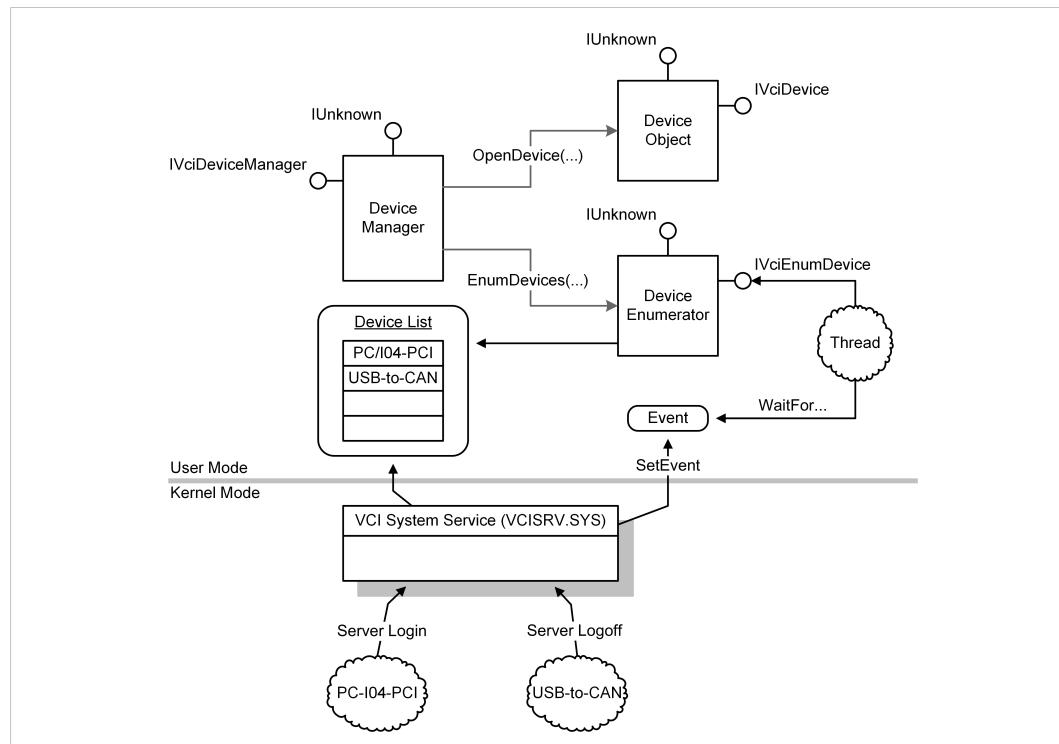


Fig. 2 Device management components

The VCI server manages all devices in a system-wide global device list. When the computer is booted or a connection between device and computer is established the device is automatically logged into the server.

If a device is no longer available for example because the connection is interrupted, the device is automatically removed from the device list.

The logged in devices are accessed via the VCI device manager or its interface

IVciDeviceManager. A pointer to this interface is provided by the exported function **VciGetDeviceManager**.

Main Device Information

Interface	Type	Description
<i>VciObject</i> <i>Id</i>	Unique ID of device	When a device logs in, it is allocated a system-wide unique ID (VCIID). This ID is required for later access to the device.
<i>DeviceClass</i>	Device class	All device drivers identify their supported device class by a worldwide unique ID (GUID). Different devices belong to different device classes, for example the USB-to-CAN belongs to a different device class as PC-I04/PCI.
<i>UniqueHardware</i> <i>Id</i>	Hardware ID	Each device has a unique hardware ID. The ID can be used to differentiate between two interfaces or to search for a device with a certain hardware ID. Remains after restart of the system. Because of that it can be stored in the configuration file and enables automatic configuration of the application after program and system start.

3.1 Listing Available Devices

- ▶ To access the global device list, call function `IVciDeviceManager::EnumDevices`.
 - Returns pointer to interface `IVciEnumDevice` of the device list.

Information about available devices can be accessed and changes in the device list can be monitored. There are different possibilities to navigate in the device list.

Requesting Information About Devices in Device List

The application must provide the required memory as a structure of type `VCIDEVICEINFO`.

- ▶ Call function `IVciEnumDevice::Next`.
 - Returns description of a device in the device list.
 - With each call the internal index is incremented.
- ▶ To get information about the next device in the device list, call function `IVciEnumDevice::Next` again.

Reset the Internal List Index

- ▶ Call function `IVciEnumDevice::Reset`.
 - Subsequent call of function `vciEnumDevice::Next` provides information about the first device in the device list again.

Skipping a Defined Number of Elements in Device List

- ▶ Call function `IVciEnumDevice::Skip`.
- ▶ Use of function only makes sense in systems with unchangeable device list, because only here the sequence of the devices is known and fix.

Hot plug-in devices like USB devices are logged in with connecting and logged out with disconnecting. The devices are also logged in or off when the operating system activates or deactivates a device driver in the device manager.

Monitoring Changes in the Device List

- ▶ Call function `IVciEnumDevice::AssignEvent`.
 - An event object is created and assigned to the device list.
 - If a device or a driver logs in or off the VCI server the event object is automatically signalized.

3.2 Accessing Individual Devices

Access individual devices with function `IVciDeviceManager::OpenDevice`.

- ▶ Specify the device ID (VCIID) of the device to be opened in parameter (to determine the device ID see [Listing Available Devices, p. 10](#)).
- Returns pointer to interface `IVciDevice` of device list.

Requesting Information About an Open Device

- ▶ Call function `IVciDevice::GetDeviceInfo`.
- Required memory is provided by the application as structure of the type `VCIDEVICEINFO`.
- Returns information about the device in device list (see [Main Device Information, p. 9](#)).

Requesting Information About Technical Features of a Device

- ▶ Call function `IVciDevice::GetDeviceCaps`.
- Parameter is pointer to structure of type `VCDEVICECAPS`.
- Function saves information about the technical features of the device in the specified area.
- Returned information informs how many bus controllers are available on a device.
- Structure `VCDEVICECAPS` contains a table with up to 32 entries, that address the respective bus connection resp. controller. Entry 0 describes the bus connection 1, entry 1 bus connection 2 etc.

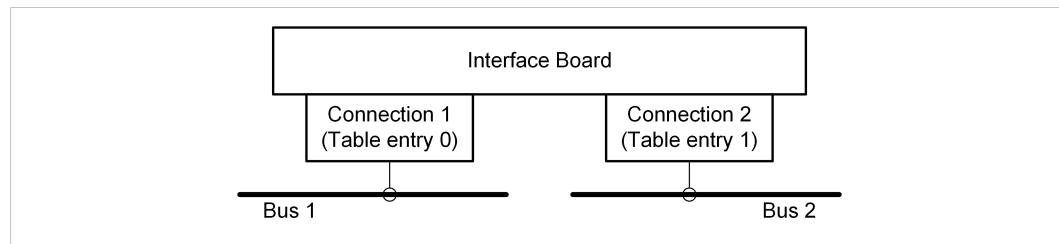


Fig. 3 Interface with two bus controllers

Opening Individual Layer Components

- ▶ With function `IVciDevice::OpenComponent` open individual layer components, which are used by different applications from different areas of applications to access the device (for further information see [Accessing the Bus Controller, p. 20](#)).

4 Communication Components

The applications communicate with the drivers resp. with the firmware running on the device with special communication components. The VCI provides diverse components for different requirements. For bus specific applications the First In/First Out memory (FIFO) is important.

Each memory used by the communication components comes from the *non-paged* memory, a part of the main memory which is not released from the operating system. This memory pool which is also used by other device drivers and by the operating system has a limited size, dependent on the version of the operating system and the available physical memory.

The 32 bit Windows variant reserves for the *non-paged* pool approx. 1/4 of the available main memory, maximum 256 MB (also in systems with more than 1 GB main memory). If the 3GB boot option is active, maximum 128 are available. The 64 bit Windows variant reserves for the *non-paged* pool approx. 400 KB per MB available main memory, maximum 128 GB.

Size of Memory Reserved for the <i>Non-Paged Pool</i> of Different Windows Versions		
	32-bit systems	64-bit systems
Windows XP, Server 2003	Up to 1.2 GB RAM: 32-256 MB, more than 1.2 GB: 256 MB	Approx. 400 KB per MB RAM, max. 128 GB
Windows Vista, Server 2008, Windows 7, Server 2008R2	Dynamically assigned, up to approx. 75 % of RAM, max. 2 GB	Dynamically assigned, up to approx. 75 % of RAM, max. 128 GB

To specify the size of the memory pool via the registry the value of *NonPagedPoolSize* has to be adjusted. This value is in:

```
HKEY_LOCAL_MACHINE
  \SYSTEM
    \CurrentControlSet
      \Control
        \Session Manager
          \Memory Management\
```



Take care of an amount and/or a size of the FIFOs as small as possible because of the limited size of the pool in 32 bit systems.

The memory actually occupied by the FIFO is dependent on the requested dimensions, but always contains at least one physical memory site, that contains 4 KB in 32 bit systems and 8 KB in 64 bit systems. Individual FIFOs can be bigger than requested. For example the calculated required memory of a FIFO with 32 elements with each 16 byte per unit is 512 byte. For the user invisible control fields are added, which in this case need additionally 24 bytes.

If such a FIFO is created in a 32 bit system, the system reserves a memory site with 4 KB. The FIFO only needs 512+24 bytes and the unused range is not used for other components due to security reasons. 3560 bytes are wasted. In FIFOs this unused range is used to increase the number of elements available to the maximum number of elements allowed for the allocated range. If a FIFO with the above stated dimensions is for example created on a 32 bit system, the FIFO has 222 additional elements, in all 254 instead of the requested 32 elements.

4.1 First In/First Out Memory (FIFO)

The VCI contains an implementation for First In/First Out memory objects.

FIFO Features:

- Dual-port memory, in which data is written on the input side and read on the output side.
- Chronological sequence is preserved, i. e. data that is written in the FIFO at first is also read at first.
- Similar to the functionality of a pipe connection and therefore also named pipe.
- Used to transfer data from a transmitter to the parallel receiver. Agreement with a lock mechanism, that has access to the common memory area at a certain point of time is not necessary.
- No locking, possible to be overcrowded, if receiver does not manage to read the data in time.
- The transmitter writes the messages to transmit with interface *IFifoWriter* in the FIFO. The receiver parallel reads the data with interface *IFifoReader*.

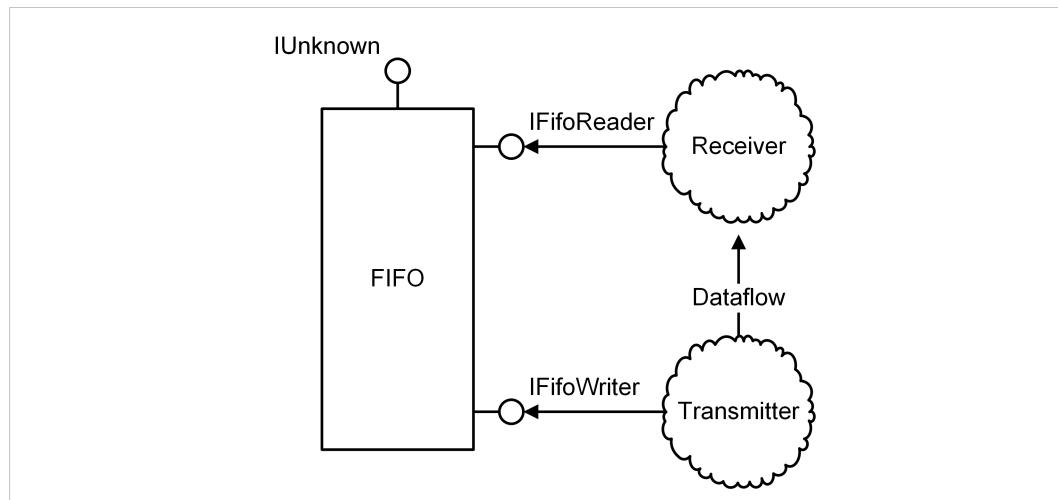


Fig. 4 FIFO data flow

Access:

- Writing and reading access to a FIFO is possible simultaneously, a receiver is able to read data while a transmitter writes new data to the FIFO.
- Simultaneous access of several transmitters resp. receivers to the FIFO is not possible.
- Multiple access to interfaces *IFifoReader* and *IFifoWriter* is prevented, because the respective interface of the FIFO can only be opened once, i. e. not until the interface is released can it be opened again.
- To prevent simultaneous access to one interface by different threads of an application:
 - ▶ Make sure that the functions of an interface can only be called by one thread of the application.
 - or
 - ▶ Synchronize the access to an interface with a respective thread: Call function `Lock` before every access to the FIFO and after accessing call function `Unlock` of the respective interface.

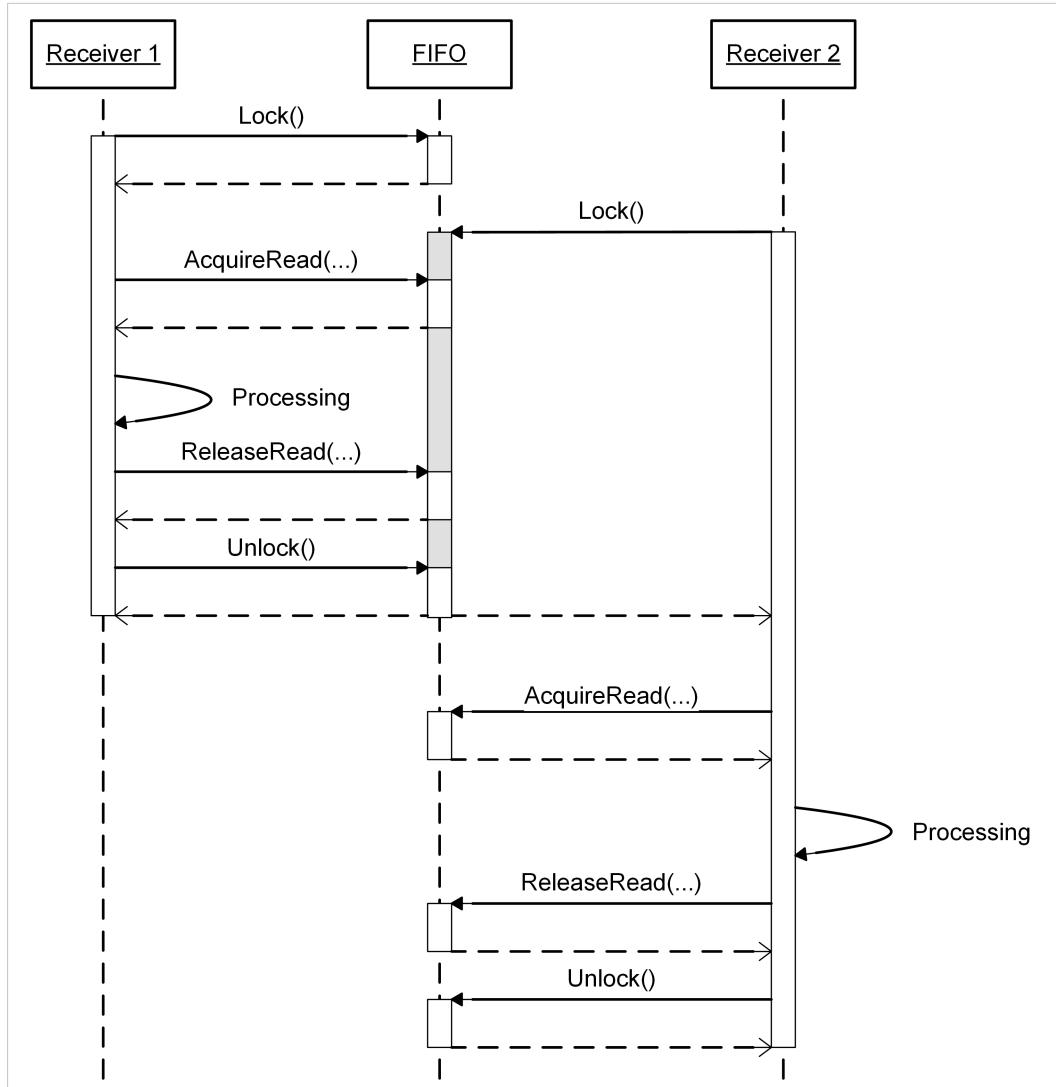


Fig. 5 FIFO locking mechanism

Receiver 1 calls function `Lock` and gains access to the FIFO. The following call of `Lock` by receiver 2 is blocked until receiver 1 releases the FIFO with calling function `Unlock`. Now receiver 2 can start processing. In the same way two transmitters that access the FIFO with the interface `IFifoWriter` can be synchronized.

The FIFOs provided by the VCI also allow the exchange of data between two processes, i. e. over the boundaries of the process.

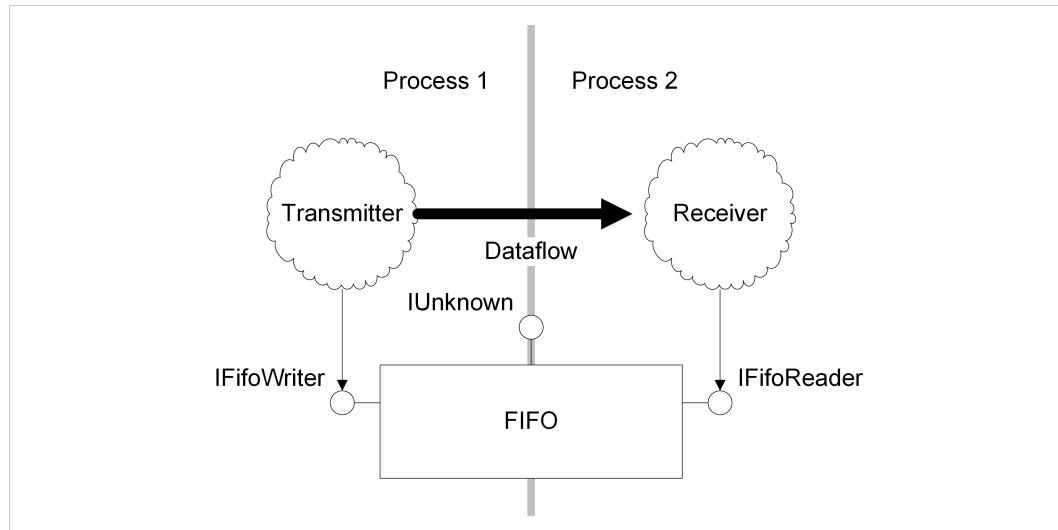


Fig. 6 FIFO for data exchange between two processes

FIFOs are also used to exchange data between components running in the kernel mode and programs running in the user mode.

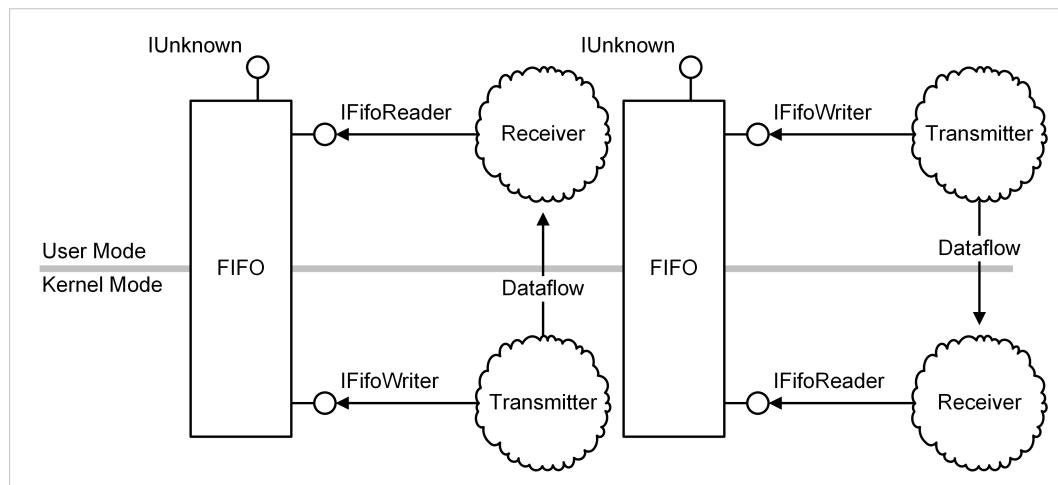


Fig. 7 Possible combination of a FIFO for data exchange between user and kernel mode

Applications can establish data channels with the functions [VciCreateFifo](#) resp. [VciAccessFifo](#) and are not dependent on operating system specific mechanisms, like *Pipes* are.

4.1.1 Functionality of the Receiving FIFO

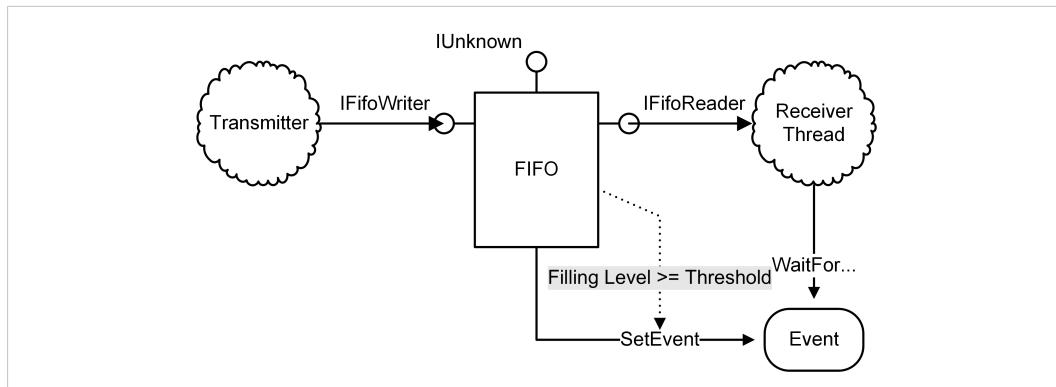


Fig. 8 Functionality of the receiving FIFO

At the receiving side FIFOs are addressed via the interface [IFifoReader](#).

Access files to read:

- ▶ Call function [GetDataEntry](#).
 - Next valid data element in the FIFO is read and released.
 - or
- ▶ Call function [AcquireRead](#).
 - Pointer to next valid element and number of valid elements that can be read sequentially from this position onward is determined.
- ▶ To release one or more read and processed elements, call function [ReleaseRead](#).

Because FIFOs reserve a sequential memory area it is possible [AcquireRead](#) returns less valid entries than are actually available.

- ▶ Repeat calling the functions [AcquireRead](#) and [ReleaseRead](#) in a loop until no more valid elements are available.

The address returned when calling [AcquireRead](#) points directly to the memory used by the FIFO.

- ▶ Make sure that no element outside the valid area is called during access.

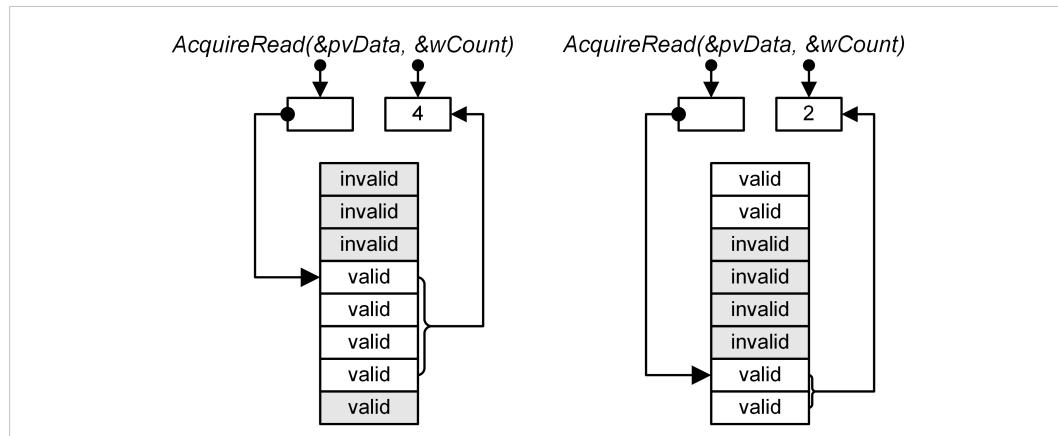


Fig. 9 Functionality of AcquireRead

Event Object

It is possible to assign an event object to the FIFO to prevent that the receiver has to ask whether new data is available for reading. The event object is set to a signaled status if a certain threshold is reached or exceeded.

- ▶ Create `CreateEvent` with Windows API function.
 - Returned handle is assigned to the FIFO with function `AssignEvent`.
- ▶ Set the threshold resp. filling level that triggers the event with function `SetThreshold`.

Afterwards the application is able to wait for the event and to read the received data with one of the Windows API functions `WaitForSingleObject`, `WaitForMultipleObjects` or one of the functions `MsgWaitFor...`

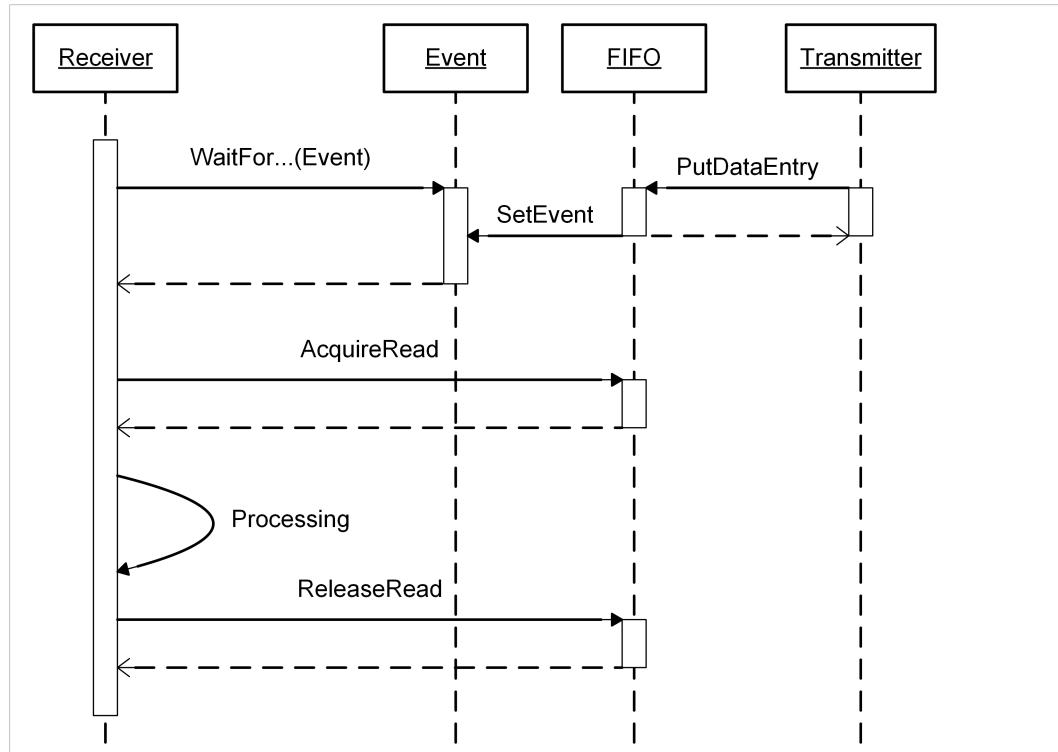


Fig. 10 Receiving sequence event-driven reading of data from the FIFO



Since the event is exclusively triggered with the exceedance of the set threshold, make sure that all entries of the FIFO are read in case of event-driven reading. If the threshold is set for example 1 and already 10 elements are in the FIFO when the event happens and only one is read, a following event will not be triggered until the next write-access. If no further write-access follows by the transmitter 9 unread elements are in the FIFO that are not shown as event anymore.

4.1.2 Functionality of the Transmitting FIFO

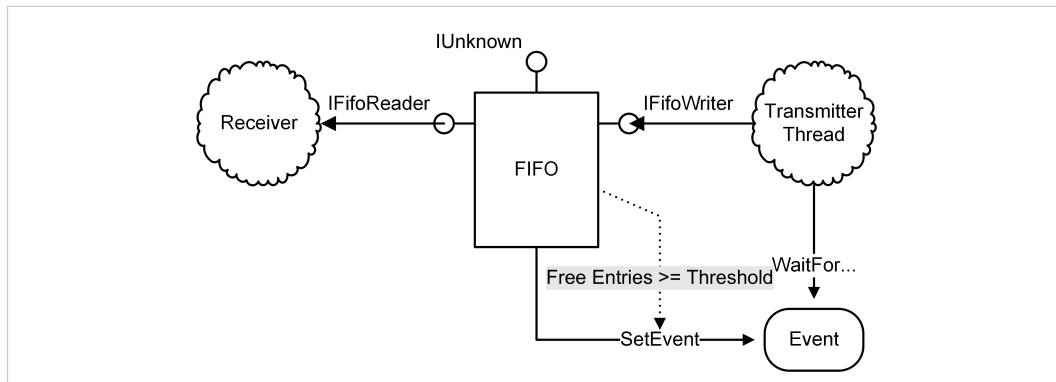


Fig. 11 Functionality of the transmitting FIFO

At the transmitting side FIFOs are addressed via the interface *IFifoWriter*.

Write data to be transmitted in the FIFO:

- ▶ To write an individual data element to the FIFO, call function *PutDataEntry*.
 - Data element is marked valid and can be read by the receiver.
 - or
- ▶ Call function *AcquireWrite*.
 - Pointer to next free element and number of free elements that can be addressed sequentially from this position onward is determined.
- ▶ Declare one or more addressed elements in the FIFO valid with function *ReleaseWrite*.
 - New elements are visible for the receiver and can be read.

Because FIFOs reserve a sequential memory area it is possible that *AcquireWrite* returns less free entries than are actually available.

- ▶ Repeat calling the functions *AcquireWrite* and *ReleaseWrite* in a loop until no more free elements are available.

The address returned when calling *AcquireWrite* points directly to the memory used by the FIFO.

- ▶ Make sure that no element outside the valid area is addressed during access.

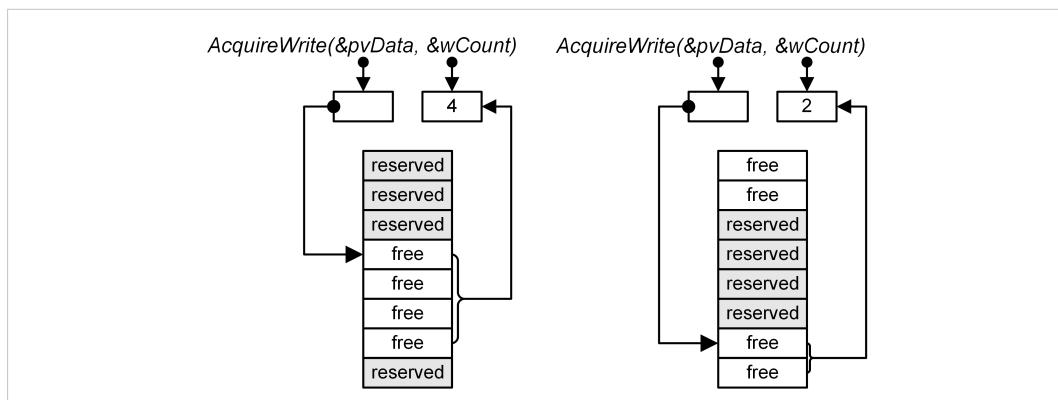


Fig. 12 Functionality of AcquireWrite

Event Object

It is possible to assign an event object to the FIFO to prevent that the transmitter must check if free elements are available. The event object is set to a signaled status if the number of free elements has reached or exceeded a certain value.

- ▶ Create `CreateEvent` with the Windows API function.
→ Returned handle is assigned to the FIFO with function `AssignEvent`.
- ▶ Set the threshold resp. number of free elements that triggers the event with function `SetThreshold`.

Afterwards the application is able to wait for the event and to write the new data in the FIFO with one of the Windows API functions `WaitForSingleObject`, `WaitForMultipleObjects` or one of the functions `MsgWaitFor...`

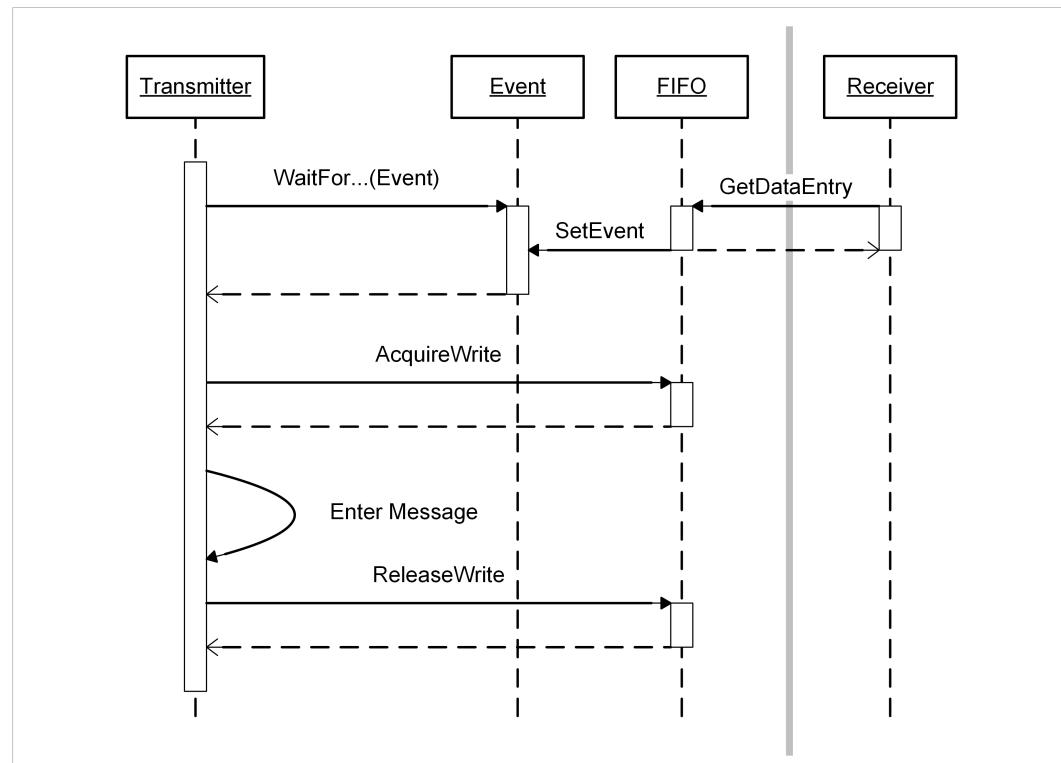


Fig. 13 Transmitting sequence event-driven writing of data to FIFO

5 Accessing the Bus Controller

Opening Individual Layer Components

With function `IVciDevice::OpenComponent` open individual layer components, which are used by different applications from different areas of applications to access the device.

- ▶ In first parameter specify which layer is opened (for further information see [OpenComponent](#)).
- ▶ In second parameter specify the interface to access.

The different layers are locked against each other and can not be opened simultaneously. If for example an application opens another layer of the BAL, no component of the BAL can be opened until all components of the other layer resp. the layer itself is closed.

5.1 BAL

The data buses that are connected via a bus adapter are accessed with the Bus Access Layer (BAL).

- Provides components and interfaces for the access to available bus controller and direct communication with the connected bus system.
- Interfaces abstract and encapsulate the communication with the controller hardware in such a way that applications can mostly be implemented independently of the special features of the different bus controllers.
- The BAL can be opened several times simultaneously (not secured against multiple opening). Different applications can access different bus connections simultaneously.

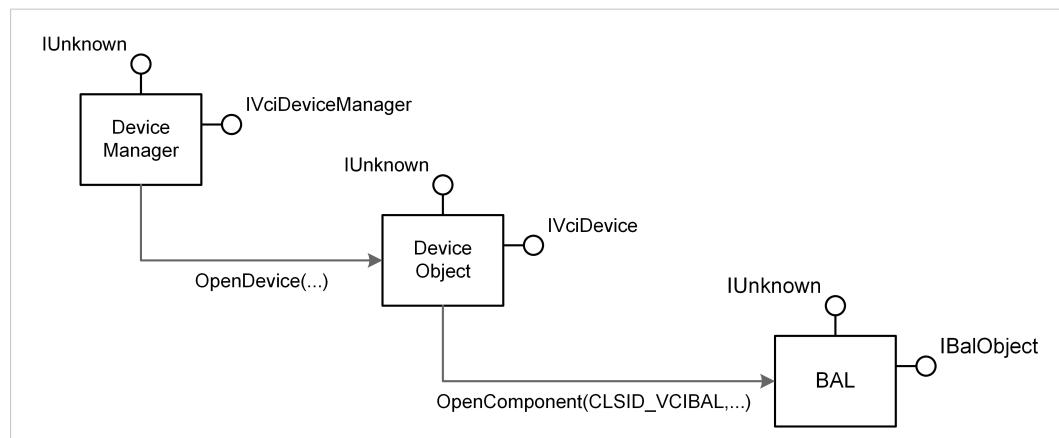


Fig. 14 Components for accessing the bus

- ▶ Search the adapter in the device list and open with `IVciDeviceManager::OpenDevice`.
- ▶ Open the BAL components with function `IVciDevice::OpenComponent`.
- ▶ In first parameter specify the value `CLSID_VCIBAL`.
- ▶ In second parameter specify the value `IID_IBalObject`, to specify the interface to access (BAL only supports interface `IBalObject`).
- ▶ Call the function.
 - Returns pointer to interfaces `IBalObject` in third parameter.
 - If an error occurs, the function returns an error code unlike `VCI_OK`.

- After opening, release the references to the device manager resp. the device object that are no longer needed with `Release`.

For further work with the adapter only the BAL object resp. its interface `IBalObject` is necessary. The interface `IBalObject` can be opened by several programs simultaneously.

The BAL object supports several types of controllers and bus connections.

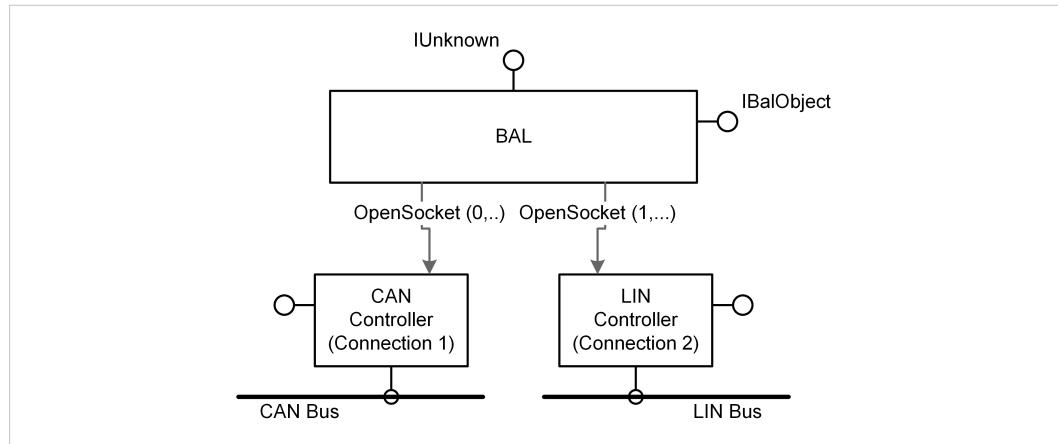


Fig. 15 BAL with CAN and LIN controller

Determine Number and Type of Provided Connections

- Call function `IBalObject::GetFeatures`.
 - Returns information as structure of type `BALFEATURES`.

Accessing the Connection or Interface of Connection

Access connection with `IBalObject::OpenSocket`.

- In the first parameter specify the number of the connection to be opened. The value must be in the range 0 to `BusSocketCount-1`. To open connection 1 enter value 0, for connection 2 value 1 etc.
- In the second parameter specify the ID of the interface to access the controller.
- Call the function.
 - Returns the address of the desired interface in the variable that points to the third parameter.
 - Possibilities resp. interfaces of a connection are dependent on the supported bus.



Certain interfaces of a connection can only be accessed by one program, others can be accessed by any number of programs simultaneously. The rules of accessing the particular interfaces are dependent on the type of the connection and are described in detail in the following chapters.

5.2 CAN Controller

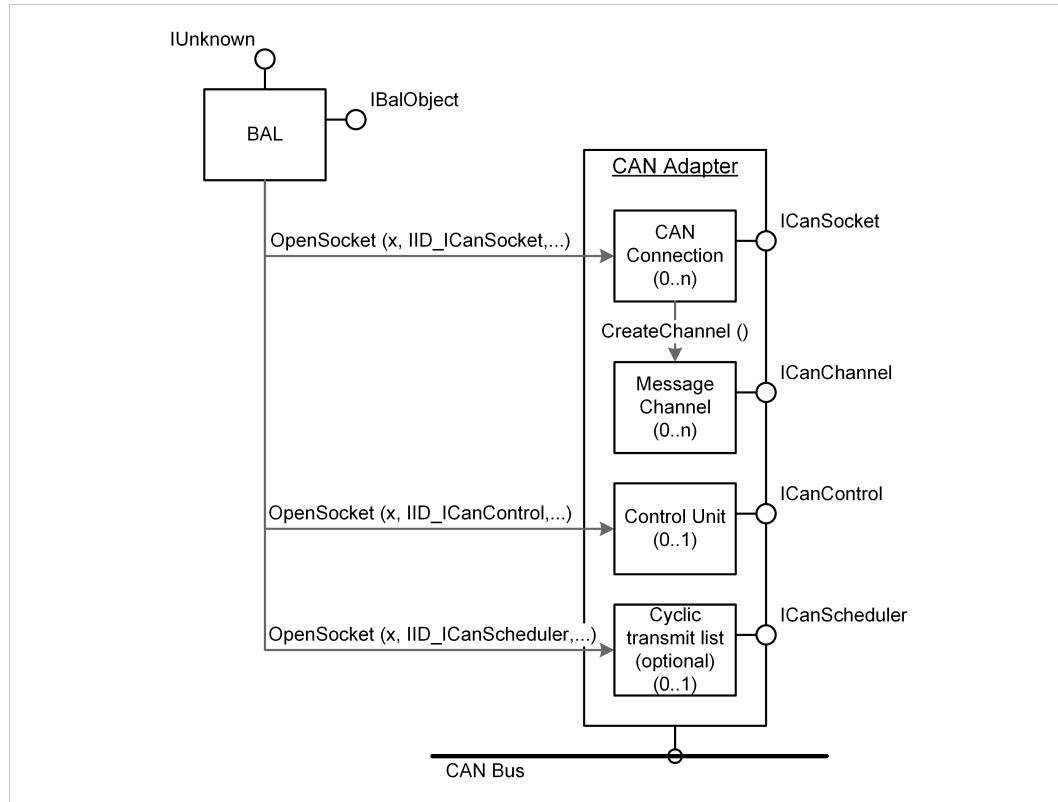


Fig. 16 Components CAN controller and interface IDs

Access individual components resp. interfaces of CAN controller with function `IBalObject::OpenSocket`. For a complete description of all interfaces and the IDs that are necessary for opening see [CAN Specific Interfaces, p. 86](#).

Supported interfaces of the components:

- `ICanSocket`, `ICanSocket2` (CAN controller), see [Socket Interface, p. 22](#).
- `ICanControl`, `ICanControl2` (control unit), see [Control Unit, p. 33](#)
- `ICanChannel`, `ICanChannel2` (message channel), see [Message Channels, p. 23](#).
- `ICanScheduler`, `ICanScheduler2` (cyclic transmitting list), see [Cyclic Transmitting List, p. 46](#), optional, exclusively with devices with their own microprocessor

The extended interfaces `ICanSocket2`, `ICanControl2`, `ICanChannel2` and `ICanScheduler2` allow the access to the new functions of CAN FD controllers. With standard controllers they can be used for further filter possibilities.

5.2.1 Socket Interface

The socket interface `ICanSocket` resp. `ICanSocket2` is used to request features, possibilities and operating status of the CAN controller. The interface is not subjected to any access restrictions and can be opened by multiple applications simultaneously.

Open with function `IBalObject::OpenSocket`.

- ▶ In parameter *riid* specify the value `IID_ICanSocket` or `IID_ICanSocket2` depending on the functionality.
- ▶ Call the function.

- ▶ To request the features of the connection, like the controller type in use, the type of bus coupling and the supported features, call function `GetCapabilities` (for further information about returned data see [CANCAPABILITIES](#) and [CANCAPABILITIES2](#)).
- ▶ To determine the current operating state of the controller, call function `GetLineStatus` (for further information see [CANLINESTATUS](#) and [CANLINESTATUS2](#)).
- ▶ Create message channels with function `CreateChannel`.

5.2.2 Message Channels

Message channels consist of a receiving and an optional transmitting FIFO.

Message channels with extended functionality (CAN FD) contain an additional, optional input filter.

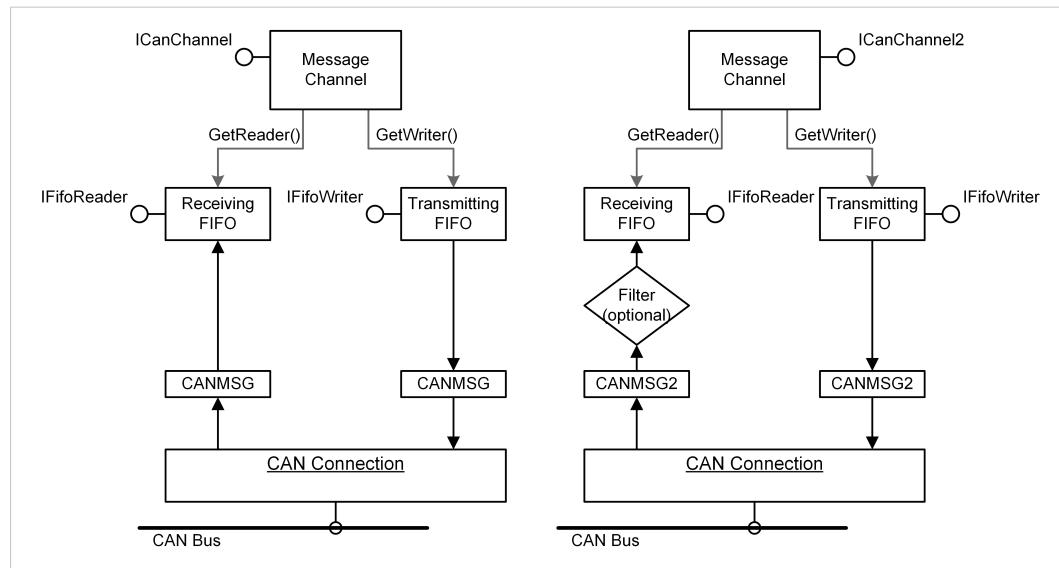


Fig. 17 Components and interfaces of a message channel

The size of the data elements in the FIFO corresponds to the size of the structure `CANMSG`, or with message channels with extended functionality the size of the structure `CANMSG2`. All functions to access the data elements of the FIFO attend resp. return a pointer to structures of type `CANMSG` resp. `CANMSG2` (description see [First In/First Out Memory \(FIFO\), p. 13](#)).

All CAN connections support message channels of the type `ICanChannel` and `ICanChannel2`. If the extended functionality of a message channel of type `ICanChannel2` is usable, is depending on the CAN controller of the connection. If the connection provides for example only a standard CAN controller, the extended functionality can not be used. With a message channel of type `ICanChannel` the extended functionality of a CAN FD can neither be used.

The basic functionality of a message channel is the same, irrespective whether the connection is used exclusively or not. If used exclusively, the message channel is directly connected to the CAN controller.

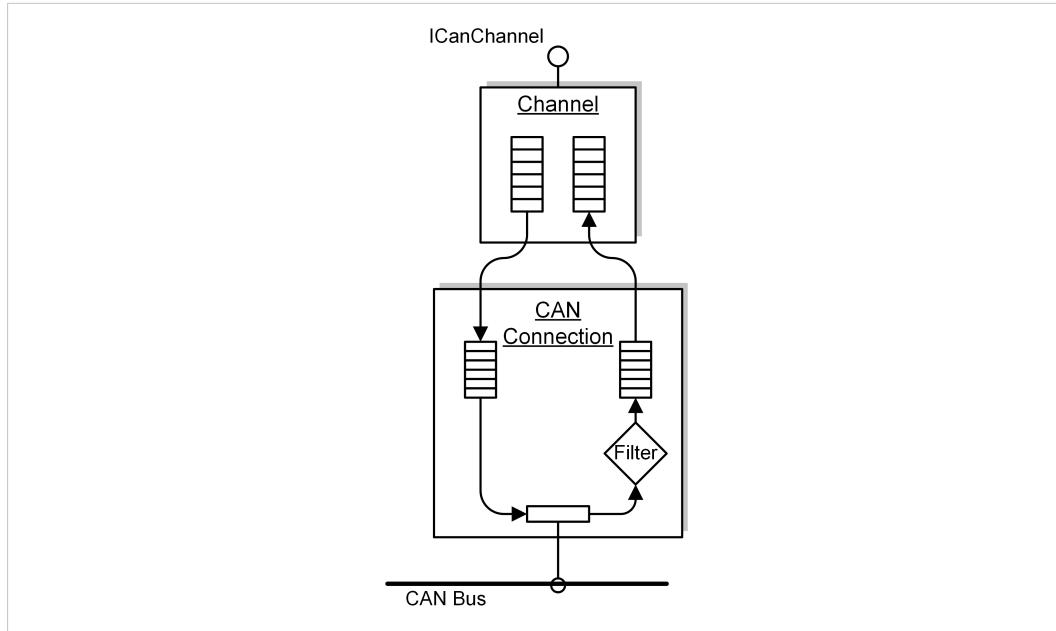


Fig. 18 Exclusive use of a message channel

In case of non-exclusive use the individual message channels are connected to the controller via a distributor.

The distributor transfers all received messages to all active channels and parallel the transmitted messages to the controller. No channel is prioritized i. e. the algorithm used by the distributor is designed to treat all channels as equal as possible.

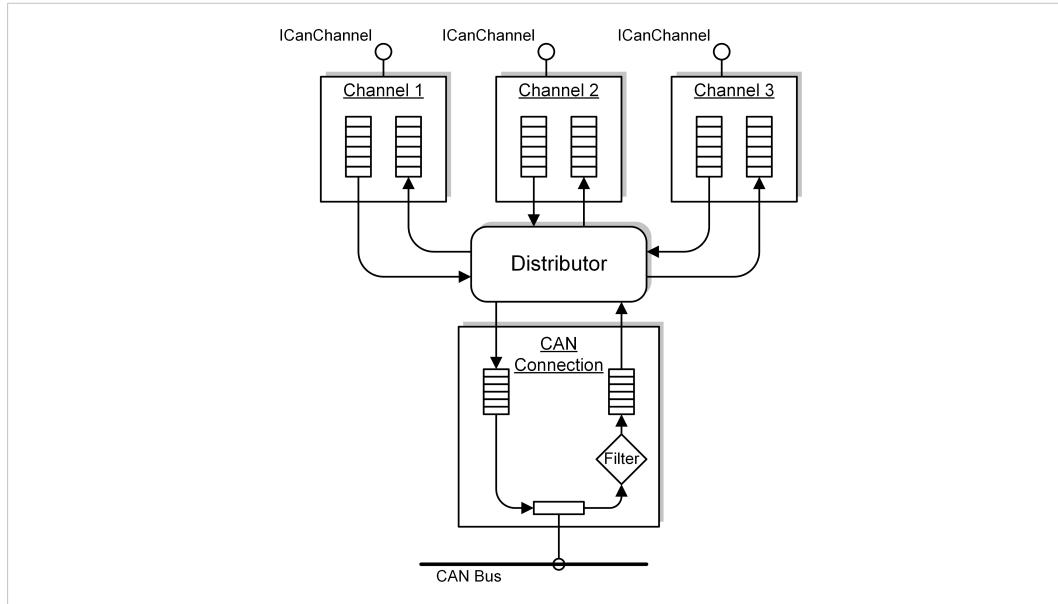


Fig. 19 CAN message distributor: possible configuration with three channels

Creating a Message Channel

Create message channel with function `ICanSocket::CreateChannel` resp. for channels with extended functionality with `ICanSocket2::CreateChannel`.

- ▶ If controller is used exclusively (exclusively with the first message channel) enter in parameter `fExclusive` the value TRUE.
 - or
 - If controller is used non-exclusively (further message channels can be opened and controller can be used by other applications) enter in parameter `fExclusive` the value FALSE.

Initializing the Message Channel

A newly generated message channel contains neither a receiving nor a transmitting FIFO. Before using an initialization is necessary.



The random access memory required for the FIFOs (see [Communication Components, p. 12](#)) limits the possible number of channels.

Initialize with function `ICanChannel::Initialize` resp. with a controller with extended functionality with `ICanChannel2::Initialize`.

- ▶ Specify the size of the receiving FIFO in parameter `wRxFifoSize` resp. `dwRxFifoSize`.
- ▶ Make sure, that the value in parameter `wRxFifoSize` is higher than 0.
- ▶ Specify the size of the transmitting FIFO in parameter `wTxFifoSize` resp. `dwTxFifoSize`.
The size determines the number of messages that the respective FIFO must record at the minimum.
- ▶ If no sending FIFO is required, set value in `wTxFifoSize` resp. `dwTxFifoSize` to 0.

If using message channels with extended functionality an additional optional receive filter can be created.

- ▶ With a 29 bit filter specify the size of the filter table in number of IDs in parameter `dwFilterSize`.
With 11 bit filter the size of the filter table is set to 2048 and can not be changed.
- ▶ If no receiving filter is needed, set `dwFilterSize` to 0.
- ▶ Specify the functionality for 11 bit and 29 bit filter in parameter `bFilterMode`.
- ▶ Call the function.



Initially specified functionality can be changed later for both filters separately with the function `SetFilterMode` in inactive message channels.

Activating the Message Channel

A new message channel is inactive. Messages can only be transmitted and received if the channel is active.

- ▶ To connect the channel to the controller and to activate the message transport, call function `Activate`.
- ▶ To activate the message transport between channel and bus, start the controller with control unit.

Which messages are received by the bus, is dependent on the settings of the message filter in the controller (further information about the control unit and message filters see [Control Unit, p. 33](#) and [Message Filter, p. 42](#)).

- ▶ Disconnect an active channel with the function `Deactivate`.

To change the filter settings of a message channel the message channel must be inactive, i. e. disconnected from the controller.

Receiving CAN Messages

The messages received on the bus and accepted by the filter are written to the receiving FIFO by the distributor.

- ▶ To access the FIFO call function `ICanChannel::GetReader` resp. with a controller with extended functionality `ICanChannel2::GetReader`.
 - Pointer to interface `IFifoReader` is returned.
 - Make sure that in all functions that return a pointer to FIFO elements the elements in the receiving FIFO are always of the type `CANMSG` resp. with a controller with extended functionality of the type `CANMSG2`.

Reading messages from the FIFO:

- ▶ Make sure that the parameter `pvData` points to a buffer of type `CANMSG` resp. `CANMSG2`.
- ▶ Call function `IFifoReader::GetDataEntry`.
 - or
- ▶ Call function `IFifoReader::AcquireRead`.
 - Returns pointer to next valid message in the FIFO and the number of messages that can be read sequentially ascending from this position onward.
- ▶ After processing remove the data with function `IFifoReader::ReleaseRead` from the FIFO.



The address returned by `AcquireRead` points directly to the memory of the FIFO. Make sure, that exclusively elements of the valid range are addressed.

Possible Use of `GetDataEntry`

```
void ReceiveMessages(IFifoReader* pReader)
{
    CANMSG sCanMsg;

    while( pReader->GetDataEntry(&sCanMsg) == VCI_OK )
    {
        // Processing of message
    }
}
```

Possible Use of AcquireRead and ReleaseRead

```
void ReceiveMessages(IFifoReader* pReader)
{
    PCANMSG2 pCanMsg2;
    UINT16 wCount;

    while( pReader->AcquireRead((PVOID*) &pCanMsg2, &wCount) == VCI_OK )
    {
        for( UINT16 i = 0; i < wCount; i++ )
        {
            // processing of message
            .
            .
            .

            // set pointer ahead to next message
            pCanMsg2++;
        }
        // release read message
        pReader->ReleaseRead(wCount);
    }
}
```

Advantages of Use of AcquireRead and ReleaseRead

- Application decides when data is copied or not.
- Application decides how many messages are removed from the FIFO.
- Useful when applications process messages only selective.

Example:

If the application detects that at a moment only two of five incoming messages can be processed, because otherwise there is an overflow somewhere else, *ReleaseRead* can be called with value 2 instead of value 5. A subsequent calling of *AcquireRead* returns a pointer to the three messages not yet processed.

Reception Time of a Message

The reception time of a message is noted in the field *dwTime* of structure [CANMSG resp. CANMSG2](#). The field contains the number of timer ticks that elapsed since the start of the timer. Dependent on the hardware the timer either starts with the start of the controller or with the start of the hardware. The time stamp of the CAN_INFO_START message (see type CAN_MSGTYPE_INFO of structure [CANMSGINFO](#)), that is written to the receiving FIFOs of all active message channels when the control unit is started, contains the starting point of the controller.

To get the relative reception time of a message (in relation to the start of the controller) subtract the starting point of the controller (see [CANMSGINFO](#)) from the absolute reception time of the message (see [CANMSG resp. CANMSG2](#)).

After an overrun of the counter the timer is reset.

Calculation of the relative reception time (T_{rx}) in ticks:

- $T_{rx} = dwTime$ of message – $dwTime$ of CAN_INFO_START (start of controller)
 - Field *dwTime* of the message see [CANMSG resp. CANMSG2](#)
 - Field *dwTime* of CAN_INFO_START see CAN_MSGTYPE_INFO of structure [CANMSGINFO](#)

Calculation of the length of a tick resp. the resolution of a time stamp in seconds: (t_{tsc}):

- $t_{tsc} [s] = dwTscDivisor / dwClockFreq$
 - Fields *dwClockFreq* and *dwTscDivisor* see [CANCAPABILITIES](#)
- Channels with extended functionality:
 $t_{tsc} [s] = dwTscDivisor / dwTscClockFreq$
 - Fields *dwTscClockFreq* and *dwTscDivisor* see [CANCAPABILITIES2](#)

Calculation of the reception time (T_{rx}) in seconds:

- $T_{rx} [s] = dwTime * t_{tsc}$

Transmitting CAN Messages

Messages are transmitted via the transmitting FIFO of the message channel.

- ▶ To access the FIFO, call interface [IFifoWriter](#) with function `ICanChannel::GetWriter` resp. with a controller with extended functionality with function `ICanChannel2::GetWriter`.

Write messages to the FIFO:

- ▶ Make sure that the parameter *pvData* points to a buffer of type [CANMSG resp. CANMSG2](#).
- ▶ Make sure that the buffer is initialized with valid values.
- ▶ Call function `IFifoWriter::PutDataEntry`.

Only messages of the type CAN_MSGTYPE_DATA can be transmitted. Messages with other values in the field *uMsgInfo.Bytes.bType* are ignored by the controller and automatically rejected. For detailed information about the field *uMsgInfo* of a CAN message see [CANMSGINFO](#).

or

- ▶ Call function `IFifoWriter::AcquireWrite`.
 - Returns pointer to the next free entry of the FIFO and the number of messages that can be addressed sequentially ascending from this position onward.

- ▶ Make sure, that exclusively data of the type *CANMSG* resp. with a controller with extended functionality of the type *CANMSG2* is copied to the pointer.
- ▶ To declare the messages that are written in the FIFO valid, call function *IFifoWriter::ReleaseWrite*.
 - Controller transmits messages to the bus.
 - Returned address points directly to the memory used by the FIFO.
- ▶ Make sure, that no element outside the valid area is addressed during access.

Possible Use of PutDataEntry

```
BOOL TransmitByte(IFifoWriter* pWriter, UINT32 dwId, UINT8 bData)
{
    CANMSG sCanMsg;

    // Initialize CAN message.
    sCanMsg.dwTime = 0; // send immediately, therefore 0
    sCanMsg.dwMsgId = dwId; // message ID (CAN-ID)

    sCanMsg.uMsgInfo.Bytes.bType = CAN_MSGTYPE_DATA;
    sCanMsg.uMsgInfo.Bytes.bReserved = 0; // reserved, always 0

    sCanMsg.uMsgInfo.Bits.srr = 0; // no Self-Reception
    sCanMsg.uMsgInfo.Bits.rtr = 0; // no Remote-Request
    sCanMsg.uMsgInfo.Bits.ext = 0; // Standard Frame Format
    sCanMsg.uMsgInfo.Bits.dlc = 1; // only1 data byte

    sCanMsg.abData[0] = bData;

    // send message
    return( pWriter->PutDataEntry(&sCanMsg) == VCI_OK );
}
```

Possible Use of `AcquireWrite` and `ReleaseWrite` with Message Channels with Extended Functionality

```
BOOL TransmitByte(IFifoWriter* pWriter, UINT32 dwId, UINT8 bData)
{
    PCANMSG2 pCanMsg2;

    if( pWriter->AcquireWrite((PVOID*) &pCanMsg2, NULL) == VCI_OK )
    {
        // Initialize CAN message.
        sCanMsg2.dwTime = 0; // send immediately, therefore 0
        pCanMsg2->_rsvd_ = 0; // reserved, always 0
        sCanMsg2.dwMsgId = dwId; // message ID (CAN-ID)

        pCanMsg2->uMsgInfo.Bytes.bType = CAN_MSGTYPE_DATA;
        pCanMsg2->uMsgInfo.Bytes.bFlags = 0; // preinitialized with 0
        pCanMsg2->uMsgInfo.Bytes.bFlags2 = 0; // preinitialized with 0

        pCanMsg2->uMsgInfo.Bits.fdr = 1; // use Fast Data bit rate
        pCanMsg2->uMsgInfo.Bits.ext = 1; // Extended Frame Format
        sCanMsg2.uMsgInfo.Bits.dlc = 1; // only1 data byte

        pCanMsg2->abData[0] = bData;

        // and send
        pWriter->ReleaseWrite(1);
        return TRUE;
    }

    return FALSE;
}
```

Transmitting Messages Delayed

A controller with set bit `CAN_FEATURE_DELAYEDTX` in field `dwFeatures` of structure `CANCAPABILITIES` resp. `CANCAPABILITIES2` supports the possibility to transmit messages delayed, with a latency between two consecutive messages.

Delayed transmission can be used to reduce the message load on the bus. This prevents that other to the bus connected participants receive too much data in too short a time, which can cause data loss in slow nodes.

- ▶ In field `dwTime` of structure `CANMSG` resp. `CANMSG2` specify the number of ticks that have to pass at a minimum before the next message is written in the transmitting buffer by the controller.

Delay Time

- Value 0 triggers no delay, that means a message is transmitted the next possible time.
- The maximal possible delay time is determined by the field `dwMaxDtxTicks` of structure `CANCAPABILITIES` resp. `CANCAPABILITIES2`, the value in `dwTime` must not exceed the value in `dwMaxDtxTicks`.

Calculation of the duration of a tick delay counter in seconds (t_{dtx})

- $t_{dtx} [s] = dwDtxDivisor / dwClockFreq$
- Channels with extended functionality:
 $t_{dtx} [s] = dwDtxDivisor / dwDtxClockFreq$
- Delay time of message in seconds (T_{delay}):
 $T_{delay} [s] = dwTime * t_{dtx}$

The specified delay time represents a minimal value as it can not be guaranteed that the message is transmitted exactly after the specified time. Also, it has to be considered that if several message channels are used simultaneously on one connection the specified value is basically exceeded because the distributor handles all channels one after another.

- If an application requires a precise time sequence use the connection exclusively.

Sending Messages Uniquely

The controller tries to transmit transmitting messages with set bit `uMsgInfo.Bits.ssm` only once. If this transmitting attempt is not successful the message is rejected and there is no automatic transmitting repetition.

This happens for example if one or more bus participants are transmitting simultaneously. If the participant that is transmitting a message with set `uMsgInfo.Bits.ssm` bit loses the bus assignment (arbitration), the message is rejected and further transmitting is not attempted.

The functionality is exclusively available if bit `CAN_FEATURE_SINGLESHOT` in field `dwFeatures` of structure `CANCAPABILITIES` resp. `CANCAPABILITIES2` is set.

Transmitting Messages with High Priority

Transmitting messages with set `uMsgInfo.Bits.hpm` bit are registered by the controller in a controller specific transmitting buffer that takes precedence over messages in the standard transmitting buffer and primarily transmits.

The functionality is only available if the bit `CAN_FEATURE_HIGHPRIOR` in field `dwFeatures` of structure `CANCAPABILITIES` resp. `CANCAPABILITIES2` is set. If the bit is used observe that messages that are already in the transmitting FIFO can not be overtaken. The functionality is of minor impact resp. can only be sensibly used if the controller is opened exclusive and the transmitting FIFO is empty before addressing a message with set bit `uMsgInfo.Bits.hpm`.

Transmitting Messages Confirmed (Self-Reception)

Transmitting messages with set `uMsgInfo.Bits.srr` bit are, after they are transmitted successfully from the controller to the bus, automatically received again and forwarded to all active message channels by the distributor. Each message channel can decide on its own how to handle this self reception messages.

Message Channel Type `ICanChannel`

- Write all self reception messages in the Receiving FIFO. Irrespective whether the message is transmitted on this or another channel on the same controller.
- Each active channel receives each transmitted self reception message (`uMsgInfo.Bits.srr` bit is always set).

Message Channel Type `ICanChannel12`

- If a self reception message is received, the channel verifies if the message originates from itself.
- If the message originates from itself, the message is written in the receiving FIFO with set `srr` bit irrespective of the current settings of the filter.
- If the messages originates from another channel of the same controller, the following processing is dependent on the current settings of the filter:
 - If while calling the function `ICanChannel12::Initialize` the operating mode is combined with the constant `CAN_FILTER_SRRA` the channel treats all self reception messages of all channels of the same controller as if they come from the same bus. The message, as it passes the message filter of the channel, is written to the receiving FIFO with deleted `srr` bit. For the application it seems as if the message has been transmitted from another controller.
 - If the message filter is initialized without the constant `CAN_FILTER_SRRA` the channel exclusively receives self reception messages that are transmitted by itself. Self reception messages transmitted via other channels are rejected. Messages that are transmitted via a channel with deleted `srr` bit are invisible for other channels on the same controller.

5.2.3 Control Unit

The control unit provides the following functions via the interface [ICanControl](#):

- configuration and control of the CAN controller
 - configuration of the transmitting features of the CAN controller
 - configuration of CAN message filters
 - starting and stopping of data transmitting
 - requesting of current operating state

To stop several competing applications from gaining control of the controller, the control unit can exclusively be opened once by one application at a time.

Opening the Interface

Open with function `IBalObject::OpenSocket`.

- ▶ In parameter *riid* specify the value `IID_ICanControl` resp. `IID_ICanControl2`.
 - If the function returns an error code like *access denied* the component is already used by another program.
 - ▶ With `Release` close the control unit and release for access by other applications.

i

If other interfaces of the controller are opened when the controller is closed, the current settings remain, i. e. a started CAN controller is not stopped automatically with calling `Release` as long as an additional message channel or the cyclic transmitting list is opened.

Controller States

The control unit resp. the CAN controller is always in one of the following states:

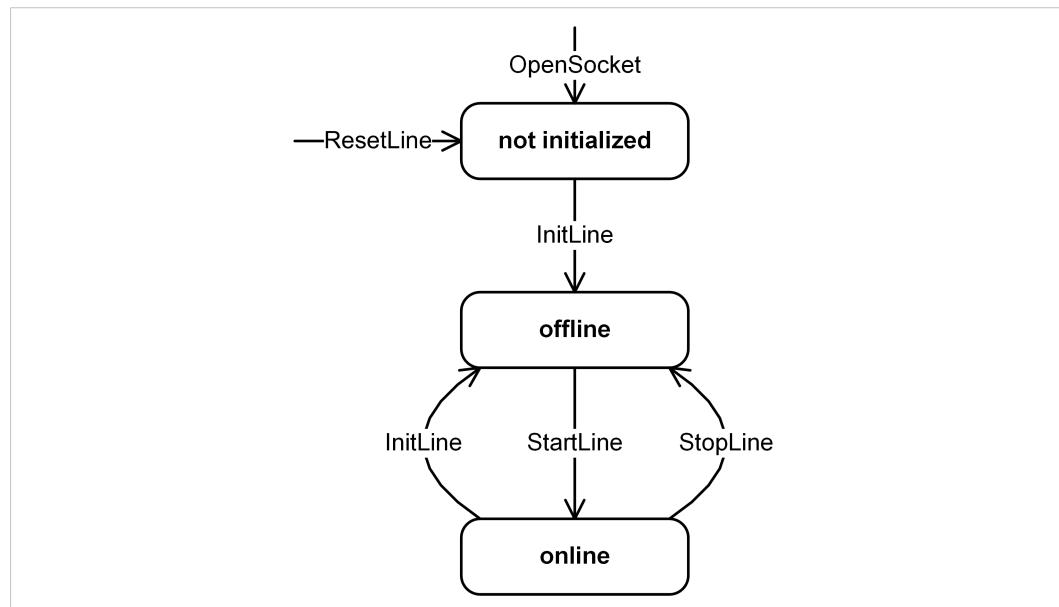


Fig. 20 Controller states

Initializing the Controller

After the first opening of the control unit via the interface `ICanControl` or `ICanControl2` the controller is in a non-initialized state.

- ▶ To leave non-initialized state, call function `ICanControl::InitLine` resp. with extended functionality `ICanControl2::InitLine`.
 - Controller is in state *offline*.
- ▶ Specify the system mode and transmission rate with function `ICanControl::InitLine` resp. `ICanControl2::InitLine`.
- ▶ Functions require in parameter `pInitParam` a pointer to a structure of `CANINITLINE` resp. `CANINITLINE2` with initialized structure.
- ▶ Specify the operating mode in field `bOpMode`.
- ▶ If a controller with extended functionality is used, activate the operating mode with field `bExMode`.
- ▶ Specify the bit rate (see [Specifying the Bit Rate, p. 35](#)).
- ▶ Call the function.
 - Controller is initialized with specified values.

Controllers with extended functionality do not have message filters with adjustable operating mode. The default and reset values for this filter operating mode are done separately for the 11 and 29 bit filter in the fields `bSFMode` and `bEFMode` (for further information see [Message Filter, p. 42](#)).

Starting the Controller

To start the CAN controller and data transmission between controller and bus:

- ▶ Make sure that the CAN controller is initialized (see [Initializing the Controller, p. 34](#)).
- ▶ Call function `StartLine`.
 - Control unit is in state *online*.
 - Incoming messages are forwarded to all active message channels.
 - Transmitting messages are transferred to the bus.

After the successful start of the controller the control unit transmits an information message to all active message channels. Field `dwMsgId` of the message contains the value `CAN_MSGID_INFO`, the field `abData[0]` the value `CAN_INFO_START` and the field `dwTime` the relative starting time.

Stopping (resp. Reset) the Controller

- ▶ Call function `StopLine`.
 - Controller is in state *offline*.
 - Data transfer between controller and bus is stopped.
 - Transport of messages between controller and all active message channels is stopped.
 - In case of an ongoing data transfer of the controller the function waits until the message is transmitted completely over the bus, before the message transmission is stopped. No faulty telegram is on the bus.

or

- ▶ Call function `ResetLine`.
 - Controller is in state *not initialized*.
 - Controller hardware and set message filters are reset to the predefined initial state.
 - Filter lists are deleted.
 - Transport of messages between controller and all active message channels is stopped.



After calling the function `ResetLine` a faulty message telegram on the bus is possible, if a not completely transferred message is in the transmitting buffer of the controller.

If `StopLine` or `ResetLine` are called the control unit transmits an information message to all active channels. The field `dwMsgId` of the message contains the value `CAN_MSGID_INFO`, the field `abData[0]` the value `CAN_INFO_STOP` resp. `CAN_INFO_RESET` and the field `dwTime` the value 0. Neither `ResetLine` nor `StopLine` delete the content of the transmitting and receiving FIFO of the message channels.

Specifying the Bit Rate

Structure `CANINITLINE`

- ▶ Specify with fields `bBtReg0` and `bBtReg1`.

The values of the fields `bBtReg0` and `bBtReg1` correspond to the values of the bus timing register `BTR0` and `BTR1` of Philips SJA1000 CAN controller with a clock frequency of 16 MHz.

Values for bit timing register BTR0 and BTR1 resp. therefore defined constants of often used bit rates:

Bit rate (KBit)	Predefined constants for BTR0, BTR1	BTR0	BTR1
5	CAN_BT0_5KB, CAN_BT1_5KB	0x3F	0x7F
10	CAN_BT0_10KB, CAN_BT1_10KB	0x31	0x1C
20	CAN_BT0_20KB, CAN_BT1_20KB	0x18	0x1C
50	CAN_BT0_50KB, CAN_BT1_50KB	0x09	0x1C
100	CAN_BT0_100KB, CAN_BT1_100KB	0x04	0x1C
125	CAN_BT0_125KB, CAN_BT1_125KB	0x03	0x1C
250	CAN_BT0_250KB, CAN_BT1_250KB	0x01	0x1C
500	CAN_BT0_500KB, CAN_BT1_500KB	0x00	0x1C
800	CAN_BT0_800KB, CAN_BT1_800KB	0x00	0x16
1000	CAN_BT0_1000KB, CAN_BT1_1000KB	0x00	0x14

For further information about `BTR0` and `BTR1` and their functionality see data sheet of Philips SJA1000.

Structure `CANINITLINE2`

Allows a more independent setting of the bit rate and the sampling time.

- ▶ Specify with the fields `sBtpSdr` and `sBtpFdr`.

The field `sBtpSdr` defines the bit timing parameters for the nominal bit rate resp. the bit rate during the arbitration period. If the controller supports fast data transfer and it is activated with the extended operating mode `CAN_EXMODE_FASTDATA` the field `sBtpFdr` determines the bit timing parameter for the fast data rate.

Time Periods

The field `dwMode` of structure `CANBTP` determines how the further fields `dwBPS`, `wTS1`, `wTS2`, `wSJW` and `wTDO` are interpreted.

If the bit CAN_BTMODE_RAW in *dwMode* is set, all other fields contain controller specific values (see [Mode CAN_BTMODE_RAW, p. 39](#)).

If the bit CAN_BTMODE_RAW is not set, the field *dwBPS* contains the desired bit rate in bits per second. The fields *wTS1* and *wTS2* divide a bit in two time periods before and after the sample time resp. the time when the controller determines the value of the bit (Sample Point).

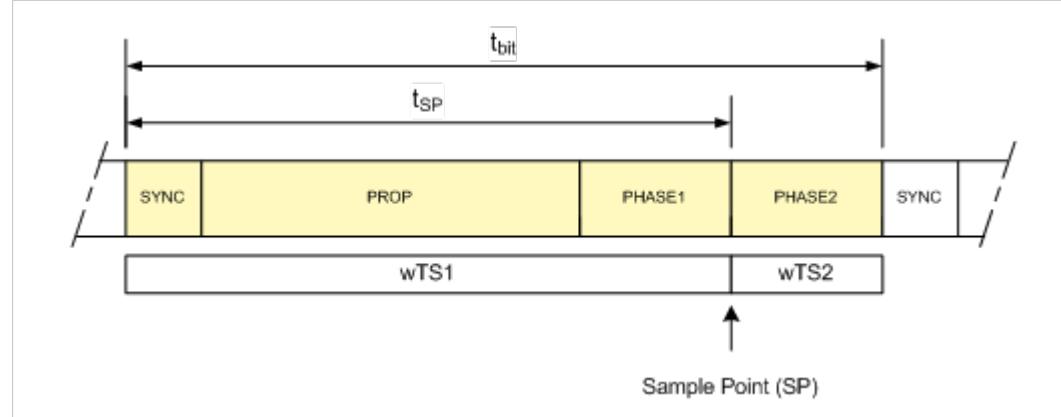


Fig. 21 Segmentation of a bit in different time periods

The amount of the fields *wTS1* and *wTS2* is the length of a bit t_{bit} and determines the number of time quanta in which a bit is divided:

- Number of time quanta per bit: $Q_{bit} = wTS1 + wTS2$

With the highest possible values for *wTS1* and *wTS2* a bit can be divided in up to $65535+65535=131070$ time quanta.

The number of time quanta per bit Q_{bit} determines together with the selected bit rate the length of an individual time quantum t_Q resp. its resolution:

- $t_Q = t_{bit} / Q_{bit} = 1 / (\text{bit rate} * Q_{bit})$

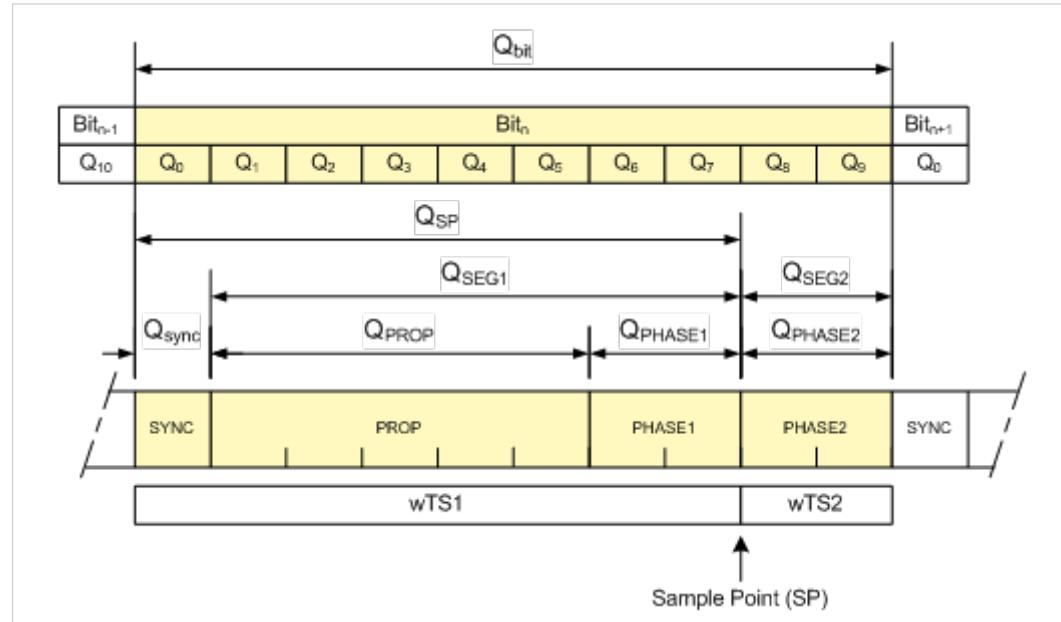


Fig. 22 Segmentation of a bit in time quanta and segments

The figure shows exemplary a segmentation in 10 time quanta. $wTS1=8$ and $wTS2=2$ is selected, with that the sample point is determined to 8/10 resp. 80 % of a bit time.

Segments

According to the CAN specification a bit is divided into the segments *SYNC*, *PROP* plus *PHASE1* and *PHASE2*. The beginning of a bit is expected in segment *SYNC*. The segment *PROP* serves as compensation to the cable and component caused delays. The segments *PHASE1* resp. *PHASE2* serve as compensation for the phase errors, that are caused for example by oscillation tolerances.

If the following recessive dominant signal flank does not occur during *SYNC* a post scoring by the controller follows. The primary scoring of the controller to the beginning of a message is always done with the starting bit of a message.

Post scoring

- Segments *PHASE1* resp. *PHASE2* are lengthened or shortened depending on the length of the phase.
- Number of time quanta (Q_{SJW}) necessary to compensate the phase errors is called synchronization jump width (*SJW*) and specified in the field *wSJW*.
- The time shifting t_{SJW} that can be compensated with that can be calculated with:

$$t_{SJW} = t_Q * wSJW$$

Synchronization Jump Width

A post scoring reduces the phase error maximally by the set synchronization jump width. If the error is not completely compensated by that a remaining phase error occurs. Because a post scoring is only done after a recessive dominant signal flank in error-free transmission it lasts maximally 10 bit times (5 dominate bits followed by 5 recessive bits) until a new recessive dominate signal flank occurs. In this 10 bit times remaining phase errors can summarize and have to be corrected by the set synchronization jump width. This results in the following condition:

Condition 1

- $2 * \Delta F * (10 * t_{bit}) \leq t_{SJW}$ (1)

In case of an error on the bus it is possible that up to 6 bits are transmitted in a row and a stuff error occurs. The controller that recognizes that at first (and is error active) then transmits an error telegram, that consists of 6 bits. Other controllers on the bus recognize this as stuff error and echo also an error telegram. On the bus a row of up to 13 dominate bits occur. In this case the next post scoring can earliest be done after 13 bit times. In this time also reset phase errors summarize. The compensation by the set synchronization jump width must be possible. This results in the second condition:

Condition 2

- $2 * \Delta F * (13 * t_{bit} - t_{PHASE2}) \leq \min(t_{PHASE1}, t_{PHASE2})$ (2)

Time Quanta

Observe the following when specifying:

- Number of time quanta inside of segment *PROP* (Q_{PROP}): choose according to the cable and component caused delays.
- The minimum number of time quanta in *PHASE1* (Q_{PHASE1}) is determined by the number of time quanta (Q_{SJW}) that are needed to compensate phase errors: must be higher than or equal the synchronization jump width.
- The minimum number of time quanta in *PHASE2* (Q_{PHASE2}) is determined by the synchronization jump width: consider processing time of the controller.
- Information processing time (*IPT*) begins with the sampling time and requires a certain amount of time quanta (Q_{IPT}): Q_{PHASE2} must be higher than or equal $Q_{IPT} + Q_{SJW}$.

The number of time quanta in the first segment until the sampling point (Q_{SP}) is equal to the sum of all time quanta in segments *SYNC*, *PROP* and *PHASE1* and is determined with the value *wTS1*. The number of time quanta in the second segment after the sampling point (Q_{SEG2}) is equal to the sum of all time quanta in segments *PHASE2* and is determined with the value *wTS2*.

The length of a time quantum t_Q also determines the value of *wSJW* and therefore is important for the post scoring resp. the compensation of phase errors.

In example *Segmentation of a bit in time quanta and segments, p. 36* with $wTS1=8$, $wTS2=2$ and $Q_{bit}=10$ the sampling point is 80 %. The resolution of a time quantum is 1/10 resp. 10 % of a bit time. If the value 1 is specified for *wSJW* the sampling point of a phase correction is shifted about ± 10 % of a bit time. Higher values than 1 are not allowed for *wSJW* in this example, because sampling errors could occur.

With a high number of time quanta phase errors can be corrected more precisely because the length of a time quanta is shortened by this.

A sampling point of 80 % can for example be reached if for *wTS1* the value 80 and for *wTS2* the value 20 ($Q_{bit}=100$) is specified. The resolution of a time quantum then is 1 % of a bit time. In this case with *wSJW*=1 phase errors up to ± 1 % of a bit time can be corrected.

The resolution of a time quantum theoretically can be shortened down to $1/131070 \approx 7.63 \cdot 10^{-6}$ resp. 7.63 ppm. As the values for the individual segments have to be converted to the hardware specific register, the limits are higher. Regarding the SJA1000 with 16 MHz clock frequency the maximum possible value for Q_{bit} is 25 (1+16+8) and therefore the minimum possible resolution is 1/25 resp. 4 % of a bit time. With higher bit times the number of time quanta is reduced and is for 1 Mbit only 8, that results in a resolution of 1/8 resp. 12.5 % of a bit time.

- ▶ To get information about the value ranges of the individual segments supported by the hardware call function `ICanSocket2::GetCapabilities`.
 - Fields *sSdrRangeMin*, *sSdrRangeMax* resp. *sFdrRangeMin* and *sFdrRangeMax* of structure *CANCAPABILITIES2* indicated with calling of the function contain hardware specific minimum and maximum values.

Mode CAN_BTMODE_RAW

- Field *dwBPS* contains the value for the frequency divider (N_P) in the CAN controller (instead of bit rate).
- Field *wTS1* contains segments *PROP* and *PHASE1* (instead of time segments *SYNC*, *PROP* and *PHASE1*)
- Number of time quanta in segment *SYNC* is fixed and always one.
- Assignments of fields *wTS2* and *wSJW* remain the same.

The following figure shows the assignment of the fields to the individual segments and the generation of the frequency for the bit processor and the resulting times.

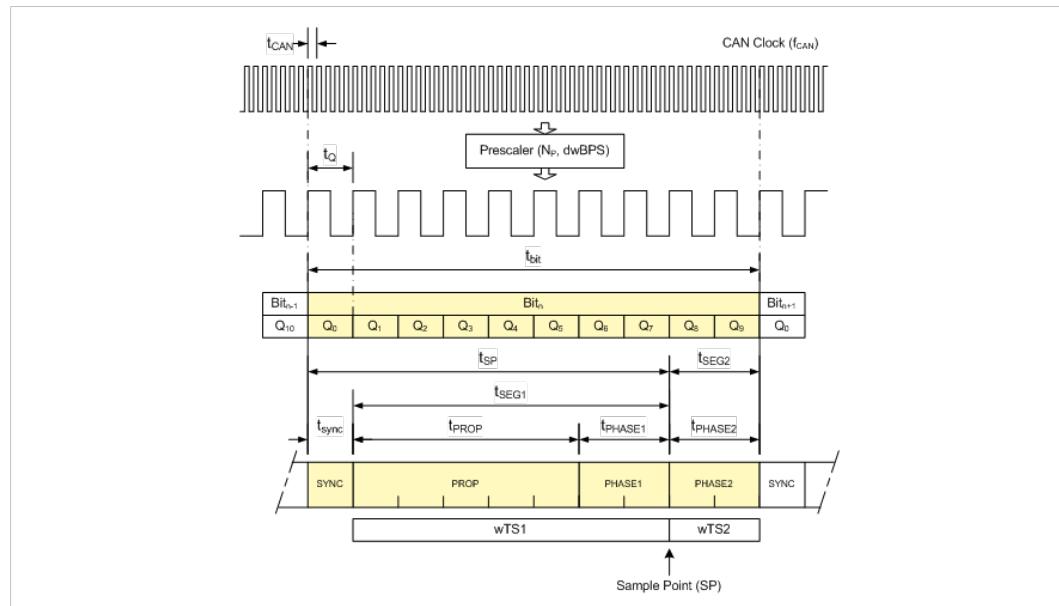


Fig. 23 Clock generator for the bit processor in the CAN controller

The field *dwCanClkFreq* of structure [CANCAPABILITIES2](#) returns the frequency of the clock generator f_{CAN} for the bit processor. This system frequency is divided by an adjustable frequency divider (prescaler). The output of the frequency divider determines the length of a time quantum t_Q :

- $t_Q = t_{CAN} * N_P = N_P / f_{CAN}$

The bit time t_{bit} is an integral multiple of a time quantum t_Q and is calculated by:

- $t_{bit} = t_Q * Q_{bit} = Q_{bit} * N_P / f_{CAN}$

The bit rate f_{bit} is calculated by:

- $f_{bit} = 1/t_{bit} = f_{CAN} / (Q_{bit} * N_P)$

To specify the bit rate f_{bit} with predefined frequency f_{CAN} the prescaler N_P and the number of time quanta Q_{bit} must be specified.

A possibility to specify the parameters is for example to begin with the maximally possible time quanta $\max(Q_{bit})$ and to determine with that the value for the prescaler N_P .

- $N_P = f_{CAN} / (f_{bit} * Q_{bit})$

If no appropriate value results for N_P , the number of time quanta is reduced by 1 and a new value for N_P is calculated. This is proceeded until either an appropriate value for N_P is found or the value has fallen below the minimal amount of time quanta $\min(Q_{bit})$.

If the value has fallen below the minimal amount of time quanta there is no solution for the demanded bit rate. In the other case with the found values for N_p and Q_{bit} the values for $wTS1$, $wTS2$ and $wSJW$ can be determined in the following way:

- ▶ Calculate the time of a time quantum:

$$t_Q = N_p / f_{CAN}$$
- ▶ Determine the amount of time quanta Q_{SJW} required for the post scoring with [Condition 1](#) and [Condition 2](#).



The value is dependent on the oscillation tolerance ΔF . The oscillation tolerance of Ixxat CAN interfaces is normally smaller than 0.1 % but in this case the greatest oscillation tolerance of all nodes existing in the network must be considered.

- ▶ To calculate the number of required time quanta for the segment $PROP$ (Q_{PROP}) divide the cable and component caused delays t_{PROP} by the length of a time quantum t_Q and round up to the next integral number:

$$Q_{PROP} = \text{round_up}(t_{PROP} / t_Q)$$

- ▶ Calculate the total number of time quanta for the phase compensation Q_{PHASE} :

$$Q_{PHASE} = Q_{bit} - (Q_{SYNC} + Q_{PROP}) = Q_{bit} - 1 - Q_{PROP}$$

Q_{PHASE1} and Q_{PHASE2} are calculated by a integral division of Q_{PHASE} by 2 and the remaining. In case of an uneven value for Q_{PHASE} the smaller part is assigned to Q_{PHASE1} and the greater to Q_{PHASE2} .

$$Q_{PHASE1} = \text{INT}(Q_{PHASE}/2)$$

$$Q_{PHASE2} = \text{INT}(Q_{PHASE}/2) + \text{MOD}(Q_{PHASE}/2)$$

If Q_{PHASE1} is less than Q_{SJW} or Q_{PHASE2} is less than $Q_{SJW} + Q_{PT}$ there is no solution for the requested bit rate. The minimum value of $sSdrRangeMin.wTS2$ resp. $sFdrRangeMin.wTS2$ corresponds to Q_{PT} .

Further information about the setting of the bit rate see CAN resp. CAN FD specification and in the CAN FD white paper of Bosch both in chapter "Bit Timing Requirements".

For information about the calculation of the parameter for the fast bit rate see CAN FD specification.

Determine the Bit Rate Used in the Network

If the CAN connector is connected to a running network with unknown bit rate the current bit rate can be determined.

- ▶ Use the CAN controller in listen only mode.
- ▶ Make sure that two further bus participants are transmitting messages.
- ▶ Call function `DetectBaud`.
 - Field `bIndex` of structure [`CANBTRTABLE`](#) contains the table index of the found bus timing values.
- ▶ The determined bus timing values can be used when calling the function `InitLine`.

Function `DetectBaud` requires a pointer to the initialized structure of type [`CANBTRTABLE`](#), that contains a predefined set of bit timing values. The extended version requires a pointer to the initialized structure of type [`CANBTPTABLE`](#), that contains a predefined set of bit timing values for the needed standard resp. nominal bit rates and eventually also for the according fast data bit rate.

Example of Use of the Function to Adjust CAN Controller Automatically to the Bit Rate of the Running System:

```
BOOL AutoInitLine( ICanControl* pControl )
{
    static UINT8 abBtr0[] =
    {
        CAN_BT0_10KB, CAN_BT0_20KB, CAN_BT0_50KB,
        CAN_BT0_100KB, CAN_BT0_125KB, CAN_BT0_250KB,
        CAN_BT0_500KB, CAN_BT0_800KB, CAN_BT0_1000KB
    };

    static UINT8 abBtr1[] =
    {
        CAN_BT1_10KB, CAN_BT1_20KB, CAN_BT1_50KB,
        CAN_BT1_100KB, CAN_BT1_125KB, CAN_BT1_250KB,
        CAN_BT1_500KB, CAN_BT1_800KB, CAN_BT1_1000KB
    };
    HRESULT hResult;
    CANBTRTABLE sBtrTab;

    // determine bit rate
    sBtrTab.bCount = sizeof(abBtr0) / sizeof(abBtr0[0]);
    sBtrTab.bIndex = 0xFF;
    memcpy(sBtrTab.abBtr0, abBtr0, sizeof(abBtr0));
    memcpy(sBtrTab.abBtr1, abBtr1, sizeof(abBtr1));

    hResult = pControl->DetectBaud(10000, &sBtrTab);
    if (hResult == VCI_OK)
    {
        CANINITLINE sInitParam;

        sInitParam. bOpMode = CAN_OPMODE_STANDARD|CAN_OPMODE_ERRFRAME;
        sInitParam. bReserved = 0;
        sInitParam. bBtReg0 = sBtrTab.abBtr0[sBtrTab.bIndex];
        sInitParam. bBtReg1 = sBtrTab.abBtr1[sBtrTab.bIndex];

        hResult = pControl->InitLine(&sInitParam);
    }

    return( hResult == VCI_OK );
}
```

5.2.4 Message Filter

All control units and message channels with expanded functionality have a two-level message filter to filter the data messages received from the bus. Information, error and status messages that are transmitted by the controller resp. the control unit always can pass unhindered.

The data messages are exclusively filtered by the ID in field `dwMsgId` of structure `CANMSG` resp. `CANMSG2`. The other fields of a message, including the data bytes in field `abData` are not considered.

Operating Modes

Message filters can be ran in different operating modes:

- Blocking mode (`CAN_FILTER_LOCK`):
Filter blocks all messages of type `CAN_MSGTYPE_DATA`, independent of the ID. Used for example if an application is only interested in information, error or status messages.
- Passing mode (`CAN_FILTER_PASS`):
Filter is completely opened and all data messages can pass. Default operating mode when using the interface `ICanChannel`.
- Inclusive filtering (`CAN_FILTER_INCL`):
All data messages with an ID either released in the acceptance filter or registered in the filter list can pass the filter (e. i. all registered IDs). Default operating mode when using the interface `ICanControl`.
- Exclusive filtering (`CAN_FILTER_EXCL`):
All data messages with an ID either released in the acceptance filter or registered in the filter list are blocked by the filter (e. i. all registered IDs).

If the interface `ICanControl` is used, the operating mode of the filter can not be changed and is preset to `CAN_FILTER_INCL`. If the interface `ICanControl2` resp. `ICanChannel2` is used, the operating mode can be set to one of the above stated modes with the function `SetFilterMode`.



To ask for the operating mode of the filter call function `GetFilterMode`.

Inclusive and Exclusive Operating Mode

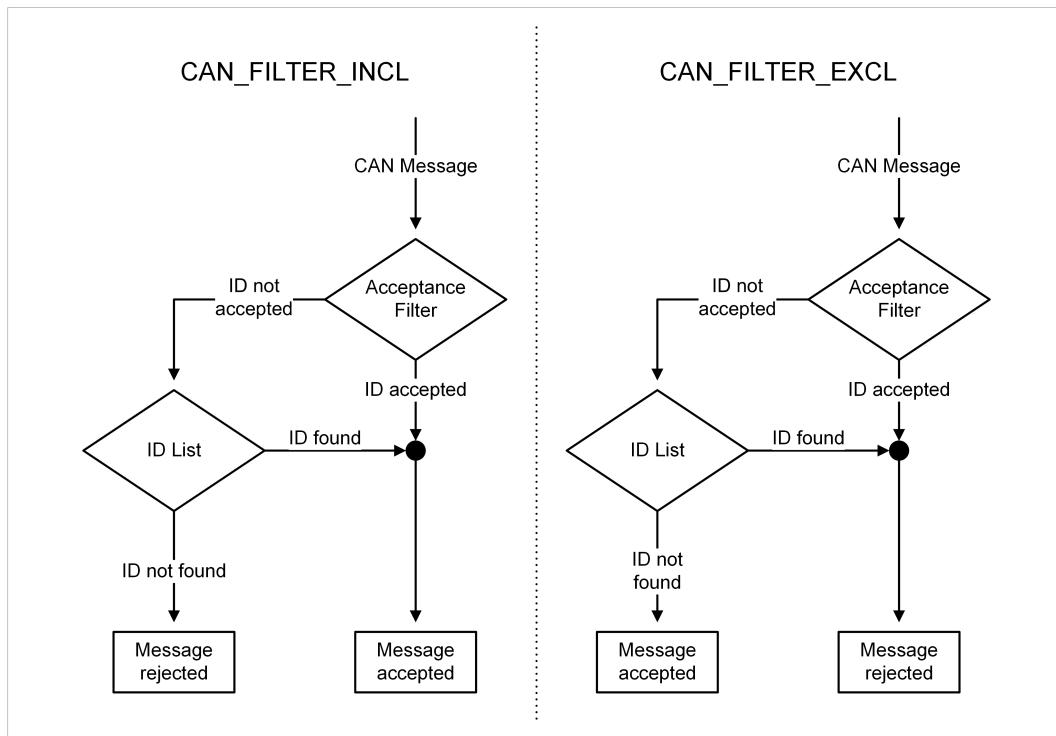


Fig. 24 Filtering mechanism inclusive and exclusive operating mode

The first filter level consists of an acceptance filter that compares the ID of a received message with a binary bit sample. If the ID correlates with the set bit sample the ID is accepted. In case of inclusive operating mode the message is accepted. In case of exclusive operating mode the message is immediately rejected.

If the first filter level does not accept the ID it is forwarded to the second filter level. The second filter level consists of a list with registered message IDs. If the ID of the received message is equal to an ID in the list, the message is accepted in case of inclusive filtering and rejected in case of exclusive filtering.

Filter Chain

Each message channel is connected to a controller either directly or indirectly via a distributor (see [Message Channels, p. 23](#)). If a filter is used both with the controller and with the message channel a multi-level filter chain is formed. Messages that are filtered out by the controller are invisible for the down-streamed channels.

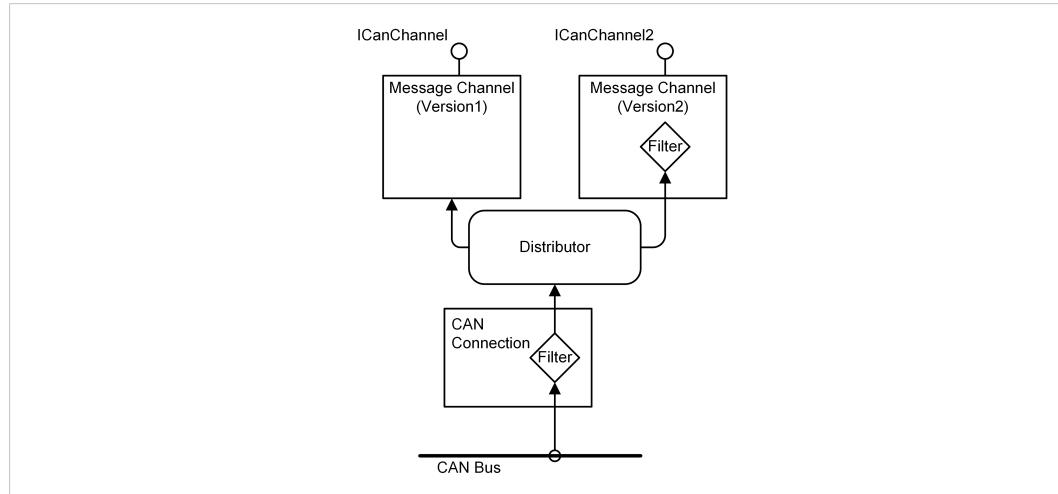


Fig. 25 Filter Chain

Setting the Filter

Control units and message channels have separated and independent filters for 11 bit and 29 bit IDs. Messages with 11 bit ID are filtered by the 11 bit filter and messages with 29 bit ID by the 29 bit filter.

To distinguish between 11 and 29 bit filter all stated functions have the parameter *bSelect*.



Changes of the filters during operation are not possible.

- ▶ Make sure that the control unit is *offline* resp. that the message channel is inactive.
- If the interfaces *ICanControl12* resp. *ICanChannel12* are used the operating mode of the filter is preset during the initialization of the component. The specified value serves simultaneously as default value for the function *ICanControl12::ResetLine*.
- ▶ To set the filter after initialization, call function *SetFilterMode*.
 - ▶ To set the acceptance filter call function *SetAccFilter*.
 - ▶ Specify the filter list with functions *AddFilterIds* and *RemFilterIds*.
 - ▶ In parameter *bSelect* select 11 or 29 bit filter.
 - ▶ In parameters *dwCode* and *dwMask* specify two bit samples that determine one or more IDs that must be registered.
 - Value of *dwCode* determines the bit sample of the ID.
 - *dwMask* determines which bits in *dwCode* are valid and used for the comparison.

If a bit in *dwMask* has the value 0 the correlating bit in *dwCode* is not used for the comparison. But if it has the value 1 it is relevant for the comparison.

With the 11 bit filter exclusively the lower 12 bits are used. With the 29 bit filter the bits 0 to 29 are used. Bit 0 of every value defines the value of the remote transmission request bit (RTR). All other bits of the 32 bit value must be set to 0 before one of the functions is called.

Correlation between the bits in the parameters *dwCode* and *dwMask* and the bits in the message ID:

11 Bit Filter												
Bit	11	10	9	8	7	6	5	4	3	2	1	0
	ID10	ID9	ID8	ID7	ID6	ID5	ID4	ID3	ID2	ID1	ID0	RTR

29 Bit Filter												
Bit	29	28	27	26	25	...	5	4	3	2	1	0
	ID28	ID27	ID26	ID25	ID24	...	ID4	ID3	ID2	ID1	ID0	RTR

The bits 1 to 11 resp. 1 to 29 of the values in *dwCode* resp. *dwMask* correspond to the bits 0 to 10 resp. 0 to 28 of the ID of a CAN message.

The following example shows the values that must be used for *dwCode* and *dwMask* to register message IDs in the range of 100 h to 103 h (of which the RTR bit must be 0) in the filter:

<i>dwCode</i>	001 0000 0000 0
<i>dwMask</i>	111 1111 1100 1
Valid IDs:	001 0000 00xx 0
ID 100h, RTR = 0:	001 0000 0000 0
ID 101h, RTR = 0:	001 0000 0001 0
ID 102h, RTR = 0:	001 0000 0010 0
ID 103h, RTR = 0:	001 0000 0011 0

The example shows that with a simple acceptance filter only individual IDs or groups of IDs can be released. If the desired identifiers do not correspond with a certain bit sample, a second filter level, a list with IDs, must be used. The amount of IDs a list can receive can be configured.

Normally the 11 bit ID list is configured in order that all 2048 possible IDs have enough space.

- ▶ Register individual IDs or groups of IDs with function `AddFilterIds`.
- ▶ If necessary remove from the list with function `RemFilterIds`.

The parameters *dwCode* and *dwMask* have the same format as showed above.

If `AddFilterIds` is called with same values as in the above example the function enters the identifier 100 h to 103 h to the list.

- ▶ To register only an individual ID in the list, specify the desired ID (including RTR bit) in *dwCode* and in *dwMask* the value 0xFFFF (11 bit ID) resp. 0x3FFFFFFF (29 bit ID).
- ▶ To disable the acceptance filter completely, when calling function `SetAccFilter` enter in *dwCode* the value `CAN_ACC_CODE_NONE` and in *dwMask* the value `CAN_ACC_MASK_NONE`.
 - Filtering is exclusively done with ID list.
 - or
- ▶ Configure the acceptance filter with the values `CAN_ACC_CODE_ALL` and `CAN_ACC_MASK_ALL`.
 - Acceptance filter accepts all IDs and ID list is ineffective.

5.2.5 Cyclic Transmitting List

With the optionally provided transmitting list of the controller up to 16 messages can be transmitted cyclically. The access to this list is limited to one application and therefore can not be used by several programs simultaneously.

Open interface with function `IBalObject::OpenSocket`.

- ▶ In parameter *riid* enter value `IID_ICanScheduler`.
- ▶ With a controller with extended functionality enter value `IID_ICanScheduler2` in parameter *riid*.
 - If function returns an error code respective *access denied* the transmitting list is already under control of another program and can not be opened again.
- ▶ To allow access for other applications, close the open transmitting list with function `Release`.
- ▶ Add message objects with `ICanScheduler::AddMessage` resp. in case of controller with extended functionality with `ICanScheduler2::AddMessage` to the list. Functions expect pointer to an initialized object of type `CANCYCLICTXMSG` resp. `CANCYCLICTXMSG2`.
 - If successfully executed both functions return the list index of the newly added transmitting object.

One controller exclusively supports one transmitting list. Irrespective if the functions of the interface `ICanScheduler` or `ICanScheduler2` are used, the list index always refers to the same list. As the interfaces are exclusively different regarding the data type of the transmitted messages, whereas the functionality is identical, only the functions of the interface `ICanScheduler` is described hereafter.

- ▶ Specify the cycle time of a message in number of ticks in field *wCycleTime* of structure `CANCYCLICTXMSG` or `CANCYCLICTXMSG2`.
- ▶ Make sure that the specified value is higher than 0 but less than or equal the value in `CANCAPABILITIES` field *dwCmsMaxTicks* of one of the structures `CANCAPABILITIES` resp. `CANCAPABILITIES2`.
- ▶ Calculate the length of a tick resp. the cycle time of the transmitting list (t_{cycle}) with values in fields *dwClockFreq* and *dwCmsDivisor* (see `CANCAPABILITIES`), resp. with extended functionality with values in fields *dwCmsClockFreq* and *dwCmsDivisor* (see `CANCAPABILITIES2`) with the following formula:

$$t_{cycle} [\text{s}] = (\text{dwCmsDivisor} / \text{dwClockFreq})$$

or

$$t_{cycle} [\text{s}] = (\text{dwCmsDivisor} / \text{dwCmsClockFreq})$$

The transmitting task of the cyclic transmitting list divides the available time in individual segments resp. time frames. The length of a time frame is exactly the same as the length of a tick resp. the cycle time (t_{cycle}).

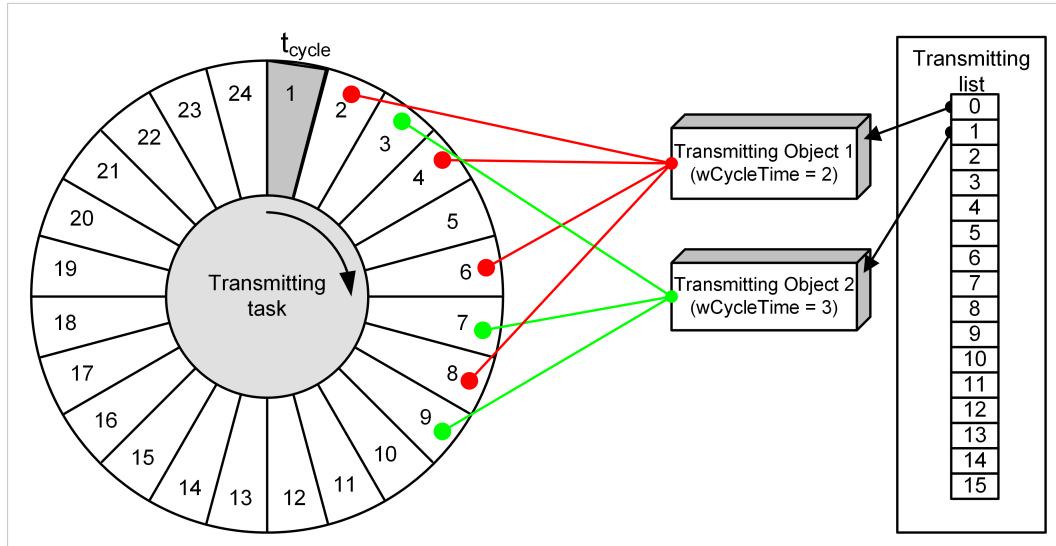


Fig. 26 Transmitting task of the cyclic transmitting list with 24 time frames

The number of the time frames supported by the transmitting task is equal to the value in field `dwCmsMaxTicks` of structure `CANCAPABILITIES` resp. `CANCAPABILITIES2`. `dwCmsMaxTicks` contains the value 24.

The transmitting task can transmit exclusively one message per tick, e. i. exclusively one transmitting object can be matched to a time frame. If the transmitting object is created with a cycle time of 1 all time frames are occupied and no other objects can be created. The more transmitting objects are created, the larger their cycle time must be selected. The rule is: The total of all $1/wCycleTime$ has to be less than 1.

In the example a message shall be transmitted every 2 ticks and a further message every 3 ticks, this amounts $1/2 + 1/3 = 5/6 = 0.833$ and therefore a valid value.

If the transmitting object 1 is created with a `wCycleTime` of 2 the time frames 2, 4, 6, 8, etc. are occupied. If the second transmitting object is created with a `wCycleTime` of 3, it leads to a collision in the time frames 6, 12, 18, etc. because these time frames are already occupied by the transmitting object 1.

Collisions are resolved in shifting the new transmitting object in the respectively next free time frame. The transmitting object of the example above then occupies the time frames 3, 7, 9, 13, 19, etc. The cycle time of the second object therefore is not met exactly and in this case leads to an inaccuracy of +1 tick.

The temporal accuracy of the transmitting of the objects is heavily depending on the message load on the bus. With increasing load the transmitting time gets more and more imprecise. The general rule is that the accuracy decreases with increasing bus load, smaller cycle times and increasing number of transmitting objects.

The field `bIncrMode` of structure `CANCYCLICTXMSG` or `CANCYCLICTXMSG2` determines if certain parts of a message are automatically incremented after transmitting or if they remain unmodified.

If in `bIncrMode` `CAN_CTXMSG_INC_NO` is specified, the content of the message remains unmodified. With the value `CAN_CTXMSG_INC_ID` the field `dwMsgId` of the message automatically increases by 1 after every transmission. If field `dwMsgId` reaches the value 2048 (11 bit ID) resp. 536.870.912 (29 bit ID) an overflow automatically takes place.

With the values `CAN_CTXMSG_INC_8` resp. `CAN_CTXMSG_INC_16` an individual 8 bit resp. 16 bit value is increment in the data field `abData[]` after each transmission. The field `bByteIndex`

of structure [CANCYCLICTXMSG](#) or [CANCYCLICTXMSG2](#) determines the starting position of the data value.

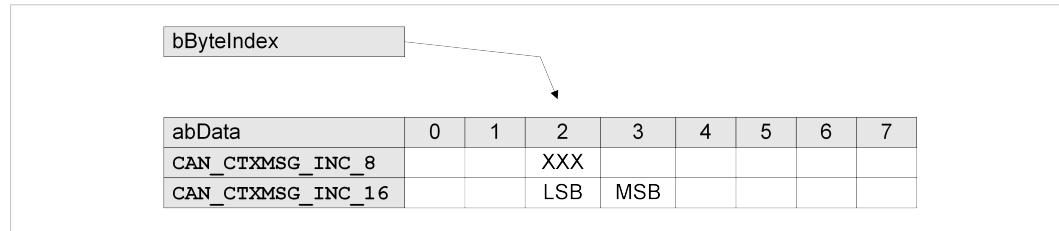


Fig. 27 Auto increment of data fields

Regarding 16 bit values, the low byte (LSB) is located in field *abData[bByteIndex]* and the high byte (MSB) in field *abData[bByteIndex+1]*. If the value 255 (8 bit) resp. 65535 (16 bit) is reached, an overflow to 0 takes place.

- ▶ If necessary, remove the transmitting object from the list with function [RemMessage](#). The function expects the list index of the object to remove returned by [AddMessage](#).
- ▶ To transmit a newly created transmitting object, call function [StartMessage](#).
- ▶ If necessary, stop transmitting with function [StopMessage](#).

The current status of the transmitting task and of all created transmitting objects is returned by the function [GetStatus](#). The required memory is provided as structure of type [CANSCHEDULERSTATUS](#) by the application. After successful execution of the function the fields *bTaskStat* and *abMsgStat* contain the state of the transmitting list and the transmitting objects.

To determine the state of an individual transmitting object the list index returned by function [AddMessage](#) is used as index in the table *abMsgStat* i. e. *abMsgStat[Index]* contains the state of the transmitting object of the specified index.

The transmitting task is deactivated after opening the transmitting list. The transmitting task does not transmit any message in deactivated state, even if the list is created and contains started transmitting objects.

- ▶ To start all transmitting objects simultaneously, configure all transmitting objects with function [StartMessage](#).
- ▶ Start a transmitting task with function [Resume](#).
- ▶ To deactivate a transmitting task call function [Suspend](#).
- ▶ To reset a transmitting task call function [Reset](#).
 - Transmitting task is stopped.
 - All registered transmitting objects are removed from the specified cyclic transmitting list.

5.3 LIN-Controller

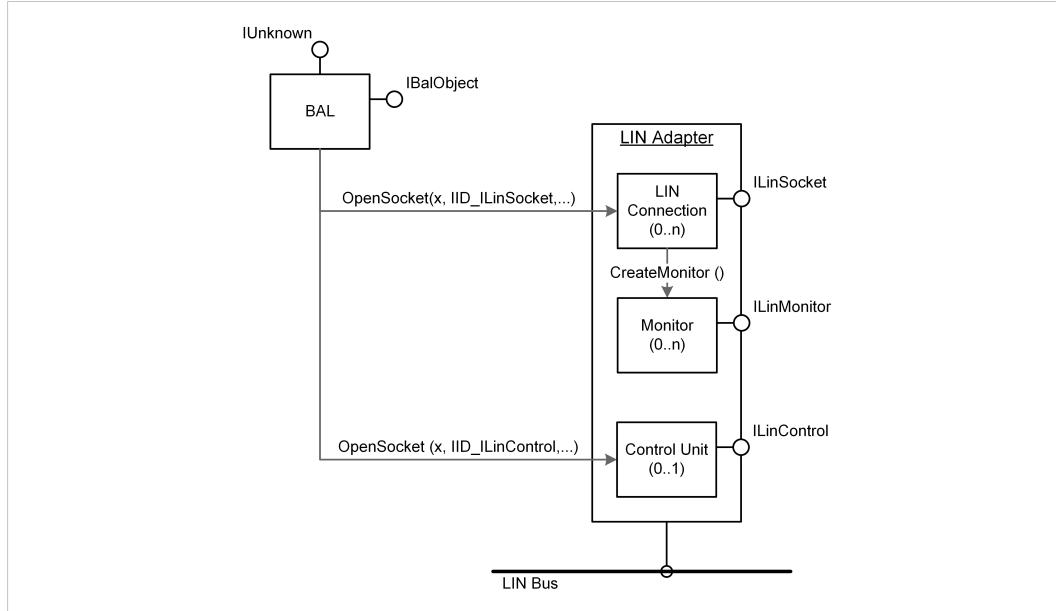


Fig. 28 Components LIN controller

- access to individual components via function `IBalObject::OpenSocket` (required IDs see figure above)
- access to individual sub components via interfaces `ILinControl` or `ILinMonitor` (see [Message Monitors, p. 50](#))

`ILinSocket` (see [Socket Interface, p. 49](#)) provides the following functions:

- requesting of LIN controller functionalities and state
- creating of message monitors, that are required for receiving messages

`ILinControl` (see [Control Unit, p. 53](#)) provides the following functions:

- configuration of LIN controller
- configuration of transmitting features
- requesting of current controller state

5.3.1 Socket Interface

The interface `ILinSocket` is not subjected to any access restrictions and can be opened by multiple applications simultaneously. Controlling via this interface is not possible.

Open with function `IBalObject::OpenSocket`.

- In parameter `riid` enter the value `IID_ILinSocket`.
- To request information about functions of the LIN controller, type of LIN controller and the supported functions, call function `GetCapabilities` (for further information see [LINCAPABILITIES](#)).
- To determine the current operating mode and status of the controller, call function `GetLineStatus` (for further information see [LINLINESTATUS](#)).
- To create message monitors, call function `CreateMonitor` (for further information see [Message Monitors, p. 50](#)).

5.3.2 Message Monitors

A LIN message monitor consists of a receiving FIFO. The size of an element in the FIFO conforms to the size of the structure [LINMSG](#).

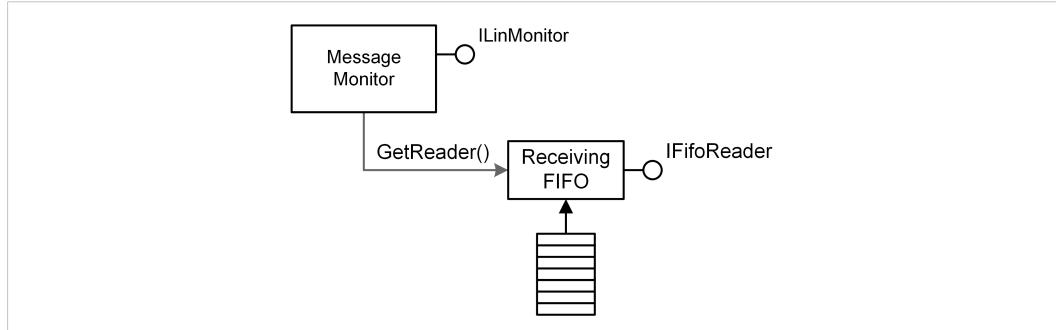


Fig. 29 Components and interfaces LIN message monitor

The functionality of a message monitor is the same, irrespective whether the connection is used exclusively or not.

In case of exclusive use the message monitor is directly connected to the LIN controller.

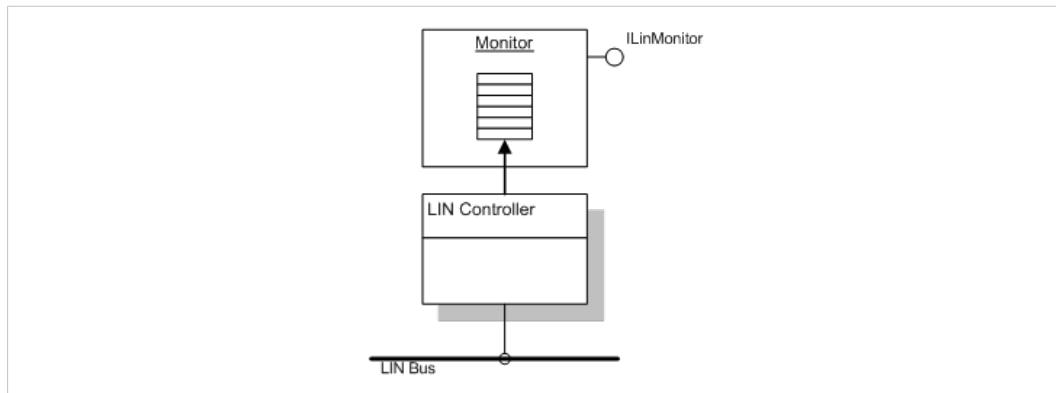


Fig. 30 Exclusive use

In case of non-exclusive use the individual message monitors are connected to the LIN controller via a distributor. The distributor transfers all on the LIN controller received messages to all active monitors. No monitor is prioritized i. e. the algorithm used by the distributor is designed to treat all monitors as equal as possible.

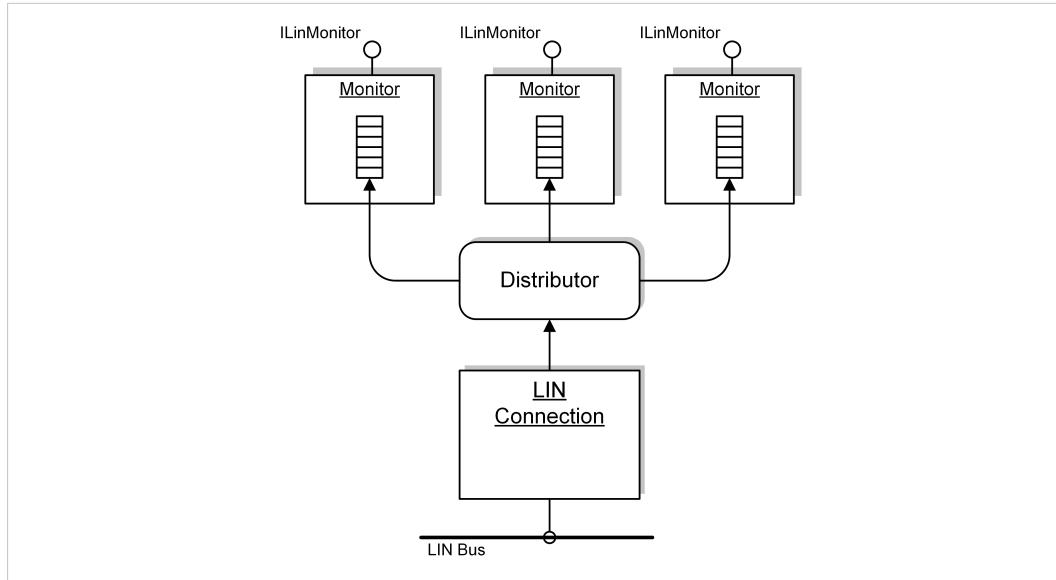


Fig. 31 Non-exclusive use (with distributor)

Creating a Message Monitor

Create a message monitor with function `ILinSocket::CreateMonitor`.

- ▶ To use the controller exclusively (only possible when creating the first message monitor) enter in parameter `fExclusive` the value TRUE. After successful execution no further message monitors can be created.
- or
- To use the controller non-exclusively (creation of any number of monitors is possible) enter in parameter `fExclusive` the value FALSE.

Initializing the Message Monitor

A newly generated message monitor contains no receiving FIFO.

- ▶ To create a receiving FIFO, call function `Initialize`.
- ▶ Specify the size of the receiving FIFO in parameter `wRxSize`.
- ▶ Make sure that the value in parameter `wRxSize` is higher than 0.

The size of an element in the FIFO conforms to the size of the structure `LINMSG`.

All functions to access the data elements of the FIFO attend resp. return a pointer to structures of type `LINMSG`.

Activating the Message Monitor

A newly generated monitor is deactivated. Messages are only received by the bus if the message monitor is active and if the LIN controller is started. Further information about LIN controllers see chapter [Control Unit, p. 53](#).

- ▶ To activate the message monitor, call function `Activate`.
- ▶ Disconnect an active monitor with function `Deactivate`.

Reading Messages From the Receiving FIFO:

- ▶ To access the receiving FIFO, call function `ILinMonitor::GetReader`.
 - Pointer to interface `IFifoReader` is returned.

Reading messages from the FIFO:

- ▶ Call function `IFifoReader::GetDataEntry`.
Make sure, that parameter `pvData` points to a buffer of type `LINMSG`.
or
- ▶ Call function `IFifoReader::AcquireRead`.
 - Returns pointer to next free message in the FIFO and the number of messages that can be read sequentially from this position onward.
 - Function returns pointer to array of type `LINMSG`.
- ▶ After processing, remove the data with function `IFifoReader::ReleaseRead` from the FIFO.



The address returned by `AcquireRead` points directly to the memory of the FIFO. Make sure that exclusively elements of the valid range are addressed.

Possible Use of `GetDataEntry`

```
void DoMessages( IFifoReader* pReader )
{
    LINMSG sLinMsg;
    while( pReader->GetDataEntry (&sLinMsg) == VCI_OK )
    {
        // Processing of message
    }
}
```

Possible Use of `AcquireRead` and `ReleaseRead`

```
void DoMessages( IFifoReader* pReader )
{
    PLINMSG pLinMsg;
    UINT16 wCount;

    while( pReader->AcquireRead((PVOID*) &pLinMsg, &wCount) == VCI_OK )
    {
        for( UINT16 i = 0; i < wCount; i++ )
        {
            // processing of message
            .
            .
            .
            // set pointer ahead to next message
            pLinMsg++;
        }

        // release read message
        pReader->ReleaseRead(wCount);
    }
}
```

5.3.3 Control Unit

The control unit provides the following functions via the interface [ILinControl](#):

- configuration of operating mode
- configuration of transmitting features
- requesting of current controller state

The control unit can exclusively be opened by one application. Simultaneous opening by several programs is not possible.

Opening the Interface

Open with function [IBalObject::OpenSocket](#).

- ▶ In parameter *riid* enter the value [IID_ILinControl](#).
 - If the function returns an error code like *access denied* the component is already used by another program.
- ▶ With [Release](#) close the control unit and release for access by other applications.



If other interfaces of the controller are opened when the controller is closed, the current settings remain, i. e. a started LIN controller is not stopped automatically with calling [Release](#) as long as an additional message monitor is opened.

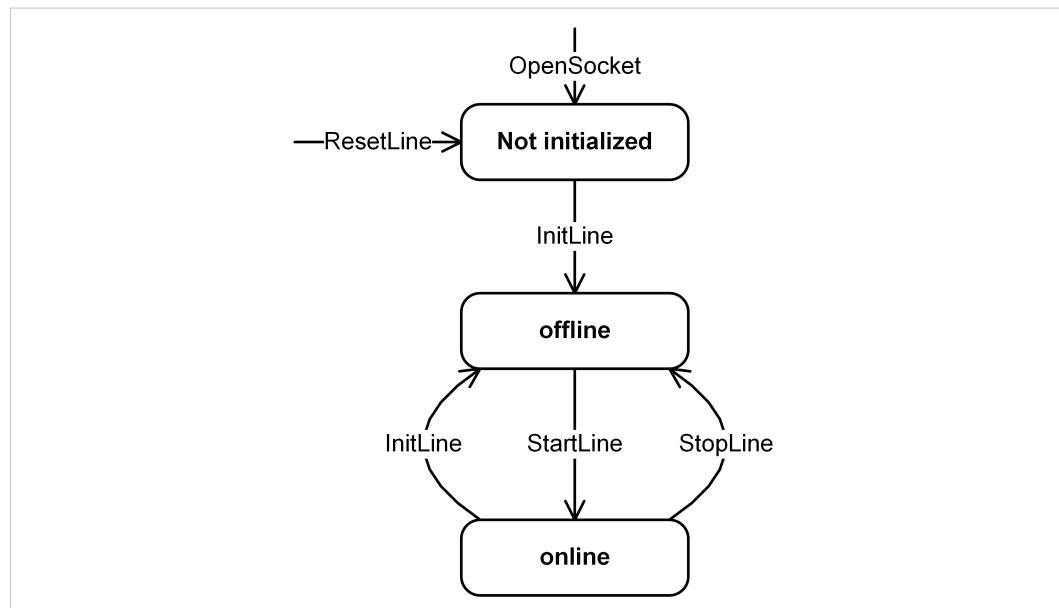


Fig. 32 LIN controller states

Initializing the Controller

After the first opening of the interface [ILinControl](#) the controller is in a non-initialized state.

- ▶ To leave a non-initialized state, call function [InitLine](#).
 - Controller is in state *offline*.
- ▶ Specify the system mode and transmission rate with function [InitLine](#).
 - Function requires in parameter *pInitParam* a pointer to an initialized structure of type [LININITLINE](#).

- ▶ Specify the transmission rate in bits per second in field `wBitrate` of structure [LININITLINE](#).

Valid values are between 1000 and 20000 Bit/s, resp. between the values specified by `LIN_BITRATE_MIN` and `LIN_BITRATE_MAX`.

If the controller supports automatic bit identification, in field `wBitrate` can be entered the value `LIN_BITRATE_AUTO` if the LIN controller is already connected to an active network.

Starting and Stopping the Controller

- ▶ To start the LIN controller, call function [StartLine](#).
 - LIN controller is in state *online*.
 - LIN controller is actively connected to bus.
 - Incoming messages are forwarded to all opened and active message monitors.
- ▶ To stop the LIN controller, call function [StopLine](#).
 - LIN controller is in state *offline*.
 - Message transfer to the monitor is interrupted and controller is deactivated.
 - In case of an ongoing data transfer the function waits until the message is transmitted completely over the bus, before the message transmission is stopped.
- ▶ Call function [ResetLine](#) to shift the controller in state *not initialized* and to reset the controller hardware.



With calling the function `ResetLine` a faulty message telegram on the bus is possible if an ongoing transmission is interrupted.

Neither [ResetLine](#) nor [StopLine](#) delete the content of the receiving FIFOs of a message monitor.

Transmitting CAN messages

Messages can be transmitted directly with the function [WriteMessage](#) or can be registered in a response table in the controller.

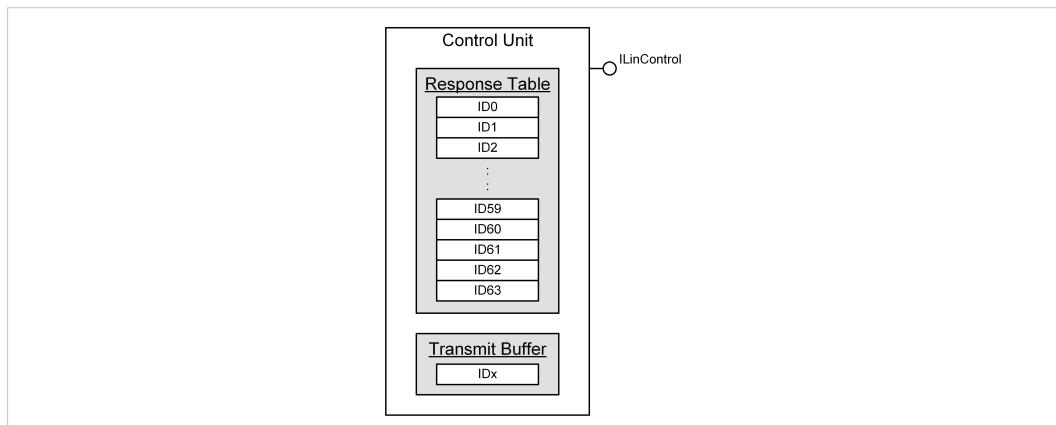


Fig. 33 Internal structure of a control unit

The control unit contains an internal response table with the response data for the IDs transmitted by the master. If the controller detects an ID that is assigned to it and transmitted by the master it transmits the response data entered in the table at the corresponding position automatically to the bus.

- ▶ To change or update the content of the response table, call function [WriteMessage](#).

- ▶ Enter in parameter *fSend* the value FALSE and in parameter *pLinMsg* a valid LIN message.
- ▶ To clear the response table, call function [ResetLine](#).

Field *abData* of structure [LINMSG](#) contains the response data. The LIN message must be of type `LIN_MSGTYPE_DATA` and must contain an ID in the range 0 to 63.

Irrespective of the operating mode (master or slave) the table must be initialized before the controller is started. The table can be updated at any time without stopping the controller.

- ▶ Transmit messages directly to the bus with function [WriteMessage](#).
- ▶ Set parameter *fSend* to value TRUE.
 - Message is registered in the transmitting buffer of the controller, instead of the response table.
 - Controller transmits message to bus as soon as it is free.

If the controller is configured as master, control messages `LIN_MSGTYPE_SLEEP` and `LIN_MSGTYPE_WAKEUP` and data messages of type `LIN_MSGTYPE_DATA` can be transmitted directly. If the controller is configured as slave exclusively `LIN_MSGTYPE_WAKEUP` messages can be directly transmitted. With all other message types the function returns an error code.

A message of type `LIN_MSGTYPE_SLEEP` generates a goto-Sleep frame, a message of type `LIN_MSGTYPE_WAKEUP` a wake-up frame on the bus. For further information see chapter Network Management in LIN specifications.

In the master mode the function [WriteMessage](#) also serves for transmitting IDs. For this a message of type `LIN_MSGTYPE_DATA` with valid ID and data length, where the bit *uMsgInfo.Bits.ido* is set to 1, is required (for further information see [LINMSGINFO](#)).

Irrespective of the value of the parameter *fSend* [WriteMessage](#) always returns immediately to the calling program without waiting for the transmission to be completed. If the function is called before the last transmission is completed or before the transmission buffer is free again, the function returns with a respective error code.

6 Error Messages

Error message	Description
LNK2001 <unresolved external problem>	GUIDs are not initialized. Include the c-file <i>uuids.c</i> from the demo, to include the header files.
LNK2005 <symbol> already defined	GUIDs are initialized in two different implementation files. Make sure that GUIDs are only initialized once.

7 Interface Description

7.1 Exported Functions

7.1.1 VciInitialize

Initializes the VCI for the calling process.

```
HRESULT VCIAPI VciInitialize ( void );
```

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

The function must be called at the beginning of a program to initialize the DLL for the calling process.

7.1.2 VciFormatError

Converts a VCI error code into a text resp. a character string that is readable for the user.

```
HRESULT VCIAPI VciFormatError (
    HRESULT hrError,
    PTCHAR pszError,
    UINT32 dwLength);
```

Parameter

Parameter	Dir.	Description
hrError	[in]	Error code that is to be converted into text.
pszError	[out]	Pointer to buffer for the text string. Function saves character string including the final 0-character in this memory area.
dwLength	[in]	Size of buffer in number of strings.

Return Value

Return value	Description
VCI_OK	Function succeeded
VCI_E_INVALIDARG	Parameter <i>pszError</i> points to invalid buffer.

7.1.3 VciGetVersion

Determines the current version numbers of the VCI and of the operating system that is currently running.

```
HRESULT VCIAPI VciGetVersion ( PVCIVERSIONINFO pVersionsInfo );
```

Parameter

Parameter	Dir.	Description
<i>pVersionsInfo</i>	[out]	Pointer to data block of type <code>VCIVERSIONINFO</code> . If run successfully the function stores the version information in this memory area.

Return Value

Return value	Description
<code>VCI_OK</code>	Function succeeded
<code>!=VCI_OK</code>	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

The function can be called at the beginning of a program to check whether the current VCI of the application is sufficient. For further information about the information that is returned by this function see description of the data structure [VCIVERSIONINFO](#).

7.1.4 VciCreateLuid

Generates a VCI-specific, unique ID.

```
HRESULT VCIAPI VciCreateLuid ( PVCIID pVciid );
```

Parameter

Parameter	Dir.	Description
<i>pVciid</i>	[out]	Pointer to variable to type <code>VCIID</code> . If run successfully the function saves the VCI-specific ID in this variable.

Return Value

Return value	Description
<code>VCI_OK</code>	Function succeeded
<code>!=VCI_OK</code>	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

Returned ID can be used during the running time of the system to mark application specific objects as unique. ID loses validity with next start of the system.

7.1.5 VciLuidToChar

The function converts a unique ID (VCIID) into a character string.

```
HRESULT VCIAPI VciLuidToChar (
    REFVCIID rVciid,
    PCHAR     pszLuid,
    LONG      cbSize );
```

Parameter

Parameter	Dir.	Description
<i>rVciid</i>	[in]	Reference to the VCI-specific unique ID to be converted (VCIID)
<i>pszLuid</i>	[out]	Pointer to buffer for the character string. If run successfully the function saves the converted VCI-specific ID in this memory area. Buffer must provide space for at least 17 characters including the final 0-character.
<i>cbSize</i>	[in]	Size in bytes of buffer specified in <i>pszLuid</i>

Return Value

Return value	Description
VCI_OK	Function succeeded
VCI_E_INVALIDARG	Parameter <i>pszLuid</i> points to invalid buffer.
VCI_E_BUFFER_OVERFLOW	The buffer specified in <i>pszLuid</i> is not large enough for the character string.

7.1.6 VciCharToLuid

Converts a 0-terminated character string into a VCI-specific unique ID (VCIID).

```
HRESULT VCIAPI VciCharToLuid (
    PCHAR     pszLuid,
    PVCIID   pVciid );
```

Parameter

Parameter	Dir.	Description
<i>pszLuid</i>	[in]	Pointer to the 0-terminated string to be converted
<i>pVciid</i>	[out]	Pointer to variable to type VCIID. If run successfully, the function returns the converted ID in this variable.

Return Value

Return value	Description
VCI_OK	Function succeeded
VCI_E_INVALIDARG	Parameter <i>pszLuid</i> or <i>pVciid</i> points to invalid buffer.
VCI_E_FAIL	In <i>pszLuid</i> specified character string can not be converted to valid ID.

7.1.7 VciGuidToChar

Converts a globally unique identifier (GUID) into a character string.

```
HRESULT VCIAPI VciGuidToChar (
    REFGUID rGuid,
    PCHAR   pszLuid,
    LONG    cbSize );
```

Parameter

Parameter	Dir.	Description
<i>rGuid</i>	[in]	Reference to the globally unique ID to be converted
<i>pszGuid</i>	[out]	Pointer to buffer for the character string. If run successfully the function saves the converted globally unique ID in this memory area. Buffer must provide space for at least 39 characters including the final 0-character.
<i>cbSize</i>	[in]	Size in bytes of buffer specified in <i>pszGuid</i>

Return Value

Return value	Description
VCI_OK	Function succeeded
VCI_E_INVALIDARG	Parameter <i>pszLuid</i> points to invalid buffer.
VCI_E_BUFFER_OVERFLOW	The buffer specified in <i>pszLuid</i> is not large enough for the character string.

7.1.8 VciCharToGuid

Converts a 0-terminated character string into a globally unique ID (GUID).

```
HRESULT VCIAPI VciCharToGuid (
    PCHAR pszGuid,
    PGUID pGuid );
```

Parameter

Parameter	Dir.	Description
<i>pszGuid</i>	[in]	Pointer to the 0-terminated string to be converted
<i>pGuid</i>	[out]	Pointer to variable to type GUID. If run successfully, the function returns the converted ID in this variable.

Return Value

Return value	Description
VCI_OK	Function succeeded
VCI_E_INVALIDARG	Parameter <i>pszGuid</i> or <i>pGuid</i> points to invalid buffer.
VCI_E_FAIL	In <i>pszGuid</i> specified character string can not be converted into a valid ID.

7.1.9 VciGetDeviceManager

Determines a pointer to the interface [IVciDeviceManager](#) of the VCI device manager.

```
HRESULT VCIAPI VciGetDeviceManager (
    IVciDeviceManager** ppDevMan );
```

Parameter

Parameter	Dir.	Description
<i>ppDevMan</i>	[out]	Address of a pointer variable. If run successfully the function saves the pointer to interface IVciDeviceManager of the VCI device manager. In case of an error the variable is set to <code>NULL</code> .

Return Value

Return value	Description
<code>VCI_OK</code>	Function succeeded
<code>!=VCI_OK</code>	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

Further information about the device manager and the exported interfaces and functions see [Interfaces of the Device Management, p. 66](#).

7.1.10 VciQueryDeviceByHwid

Opens a device or controller with a particular hardware ID.

```
HRESULT VCIAPI VciQueryDeviceByHwid (
    REFGUID rHwid,
    IVciDevice** ppDevice );
```

Parameter

Parameter	Dir.	Description
<i>rHwid</i>	[in]	Reference to hardware ID of the controller to be opened.
<i>ppDevice</i>	[out]	Address of a pointer variable. If run successfully the function saves the pointer to interface IVciDevice of the VCI device manager. In case of an error the variable is set to <code>NULL</code> .

Return Value

Return value	Description
<code>VCI_OK</code>	Function succeeded
<code>!=VCI_OK</code>	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

Every device or bus controller has a distinct hardware ID, that stays valid after the system is restarted.

7.1.11 VciQueryDeviceByClass

Opens a device or controller with a particular device class.

```
HRESULT VCIAPI VciQueryDeviceByClass (
    REFGUID      rClass
    UINT32       dwInst,
    IVciDevice** ppDevice );
```

Parameter

Parameter	Dir.	Description
rClass	[in]	Reference to class ID of the controller to be opened.
dwInst	[in]	Number of controller to be opened. If several controllers of the same class are present, this value determines the number of the controller to be opened in the device list. Value 0 selects the first controller of the specified class.
ppDevice	[out]	Address of a pointer variable. If run successfully the function saves the pointer to interface IVciDevice of the opened device or adapter. In case of an error the variable is set to <code>NULL</code> .

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

Every bus controller is assigned to a distinct device class. The instance number of this controller is not fixed, but changes dependent on when or how the controller was activated or generated by the system. This is to be considered if USB or other external controllers are used, because these can be plugged in and off during the system is running.

7.1.12 VciCreateFifo

Creates a new FIFO and determines a pointer to one of the interfaces [IVciFifo](#) resp. [IVciFifo2](#), [IFifoReader](#) or [IFifoWriter](#).

```
HRESULT VCIAPI VciCreateFifo (
    PVCIID pResid,
    UINT16 wCapacity,
    UINT16 wElementSize,
    REFIID riid,
    PVOID* ppv );
```

Parameter

Parameter	Dir.	Description
pResid	[out]	Pointer to variable of type VCIID. If run successfully the VCI-specific individually unique ID is stored by newly generated FIFO. This ID can be used for further calls of the function VciAccessFifo to reach additional interfaces of the FIFO.
wCapacity	[in]	Number of elements in the newly generated FIFO
wElementSize	[in]	Size of an element in number of bytes
riid	[in]	ID of the interface to access the component. FIFOs support the interface IDs IID_IFifoReader, IID_IFifoWriter and IID_IVciFifo resp. IID_IVciFifo2.
ppv	[out]	Address of a pointer variable. If run successfully the pointer is stored in the in <code>riid</code> requested interface. If the FIFO cannot be generated or if the FIFO does not support the interface specified in <code>riid</code> variable is set to <code>NULL</code> .

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

FIFOs occupy more than ($wCapacity * wElementSize$) bytes. The calculated size is always rounded up to the whole memory sites, with the result that the FIFO eventually contains more element than requested (further information about the memory consumption see [Communication Components, p. 12](#)).

7.1.13 VciAccessFifo

Opens an existing FIFO and requests one of the interfaces [IVciFifo](#) resp. [IVciFifo2](#), [IFifoReader](#) or [IFifoWriter](#).

```
HRESULT VCIAPI VciAccessFifo (
    REFVCIID rResid,
    REFIID    riid,
    PVOID*    ppv );
```

Parameter

Parameter	Dir.	Description
rResid	[in]	Reference to the VCI-specific ID of the FIFO to be opened.
riid	[in]	ID of the interface to access the component. FIFOs support the interface IDs IID_IFifoReader, IID_IFifoWriter and IID_IVciFifo resp. IID_IVciFifo2.
ppv	[out]	Address of a pointer variable. If run successfully the pointer is stored in the in <i>riid</i> requested interface. If the interface specified in <i>riid</i> is not supported, the FIFO cannot be opened or access is not possible, the variable is set to NULL.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

The interface [IFifoReader](#) resp. [IFifoWriter](#) can exclusively be opened once at a certain time. If the requested interface is already used the call fails. The anew opening of the interface is not possible until it is released.

7.2 Interface IUnknown

All components provided by the VCI implement the interface `IUnknown` specified in the Component Object Model of Microsoft (MS-COM). The interface provides besides the function `QueryInterface` to request further interfaces of the component, additionally the functions `AddRef` resp. `Release` to control the lifespan of the component.

7.2.1 QueryInterface

Via this function a particular interface of a component can be called.

```
ULONG QueryInterface ( REFIID riid, PVOID *ppv );
```

Parameter

Parameter	Dir.	Description
<i>riid</i>	[in]	Reference to the ID of the interface to access the component.
<i>ppv</i>	[out]	Address of a pointer variable. If run successfully the pointer is stored in the in <i>riid</i> requested interface. In case of an error the variable is set to NULL.

Return Value

Return value	Description
<code>VCI_OK</code>	Function succeeded
<code>!=VCI_OK</code>	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

If run successfully the function increments the reference counter of the component automatically by 1. When the application do not need the interfaces resp. the components any more, the pointer returned in *ppv* must be released with [Release](#).

7.2.2 AddRef

Increments the reference count of the component by 1.

```
ULONG AddRef ( void );
```

Return Value

Function returns the current value of the reference count.

Remark

The function always must be called, if the application stores a copy of the interface pointer. With this it is ensured that the component exists as long as the last reference to it is released. An interface resp. the connected component is released by the call of the function [Release](#).

7.2.3 Release

The function decrements the reference count of the component by 1. If the reference count falls to 0 the component is released.

```
ULONG Release ( void );
```

Return Value

Function returns the current value of the reference count.

Remark

After calling the function the pointer to the interface used by the application is not valid any longer and must not be used anymore. This also applies if the function returns a value larger than 0, i. e. the component itself is not released by this call.

7.3 Interfaces of the Device Management

7.3.1 IVciDeviceManager

The interface is used to access the VCI device manager. A pointer to this interface is provided by the API function `VciGetDeviceManager`. The ID of the interface is `IID_IVciDeviceManager`.

EnumDevices

Creates an object to list all devices registered on VCI.

```
HRESULT EnumDevices( IVciEnumDevice** ppEnumDevice )
```

Parameter

Parameter	Dir.	Description
<code>ppEnumDevice</code>	[out]	Address of a pointer variable. If run successfully the function saves the pointer to interface <code>IVciEnumDevice</code> of the device list. In case of an error the variable is set to <code>NULL</code> .

Return Value

Return value	Description
<code>VCI_OK</code>	Function succeeded
<code>!=VCI_OK</code>	Error, further information about error code provides the function <code>VciFormatError</code>

OpenDevice

Opens a device.

```
HRESULT OpenDevice (
    REFVCIID     rVciidDev,
    IVciDevice** ppDevice )
```

Parameter

Parameter	Dir.	Description
<code>rVciidDev</code>	[in]	Reference to the unique ID of the controller to be opened.
<code>ppDevice</code>	[out]	Address of a pointer variable. If run successfully the function saves the pointer to interface <code>IVciDevice</code> of the VCI device manager. In case of an error the variable is set to <code>NULL</code> .

Return Value

Return value	Description
<code>VCI_OK</code>	Function succeeded
<code>!=VCI_OK</code>	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

ID of device to be opened can be determined with function `IVciEnumDevice::Next` (see [Listing Available Devices, p. 10](#)).

7.3.2 IVciEnumDevice

The interfaces serves for listing all devices that are currently registered in the VCI (functionality see [Listing Available Devices, p. 10](#)) The ID of the interface is IID_IVciEnumDevice.

Next

Determines the description of one or more devices in the device list and increments an internal index, with the result that a subsequent call of the function returns the description to the respectively next devices.

```
HRESULT Next (
    UINT32          dwNumElem,
    PVCIDEVICEINFO  paDevInfo,
    PUINT32         pdwFetched );
```

Parameter

Parameter	Dir.	Description
<i>dwNumElem</i>	[in]	Number of list elements that are to be determined with this call.
<i>paDevInfo</i>	[out]	Pointer of array of minimum <i>dwNumElem</i> elements of type VCIDEVICEINFO . If run successfully the function stores the individual information about the devices in this memory area.
<i>pdwFetched</i>	[out]	Pointer to variable in which the function saves the actually determined elements if ran successfully.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError
VCI_E_NO_MORE_ITEMS	No further elements available or end of list is reached.

Remark

In Parameter *pdwFetched* the function can be applied into the value `NULL` if in parameter *dwNumElem* value 1 is specified.

Skip

Skips a certain number of entries in the device list.

```
HRESULT Skip ( UINT32 dwNumElem );
```

Parameter

Parameter	Dir.	Description
<i>dwNumElem</i>	[in]	Number of elements to be skipped

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

The function is only useful in static lists, because in static lists the order of the devices is fixed during the runtime.

Reset

Resets the internal index to initial state, with the result that a subsequent call of `Next` returns again the first element of the list.

```
HRESULT Reset ( void );
```

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function <code>VciFormatError</code>

AssignEvent

Assigns an *Event* to the device list, that is always set in signalized state when a device is added to or deleted from the list.

```
HRESULT AssignEvent ( HANDLE hEvent );
```

Parameter

Parameter	Dir.	Description
<code>hEvent</code>	[in]	Handle of event object. Specified handle must originate of Windows function <code>CreateEvent</code> .

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function <code>VciFormatError</code>

7.3.3 IVciDevice

The interface provides functions to request general information and to open application specific components of an adapter. The ID of the interface is IID_IVciDevice.

GetDeviceInfo

Determines general information about a device.

```
HRESULT GetDeviceInfo ( PVCIDEVICEINFO pInfo );
```

Parameter

Parameter	Dir.	Description
pInfo	[out]	Pointer to data block of type VCIDEVICEINFO. If run successfully the function stores the information about the device in this memory area.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

For further information about the data returned by this function see [VCIDEVICEINFO](#).

GetDeviceCaps

Determines information about the technical capabilities of a device.

```
HRESULT GetDeviceCaps ( PVCIDECAPSCAPS pCaps );
```

Parameter

Parameter	Dir.	Description
pCaps	[out]	pointer to data block of type VCIDECAPSCAPS. If run successfully the function stores the information about the technical capabilities in this memory area.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

For further information about the data returned by this function see [VCIDECAPSCAPS](#).

OpenComponent

Opens an application specific component of the adapter.

```
HRESULT OpenComponent (
    REFCLSID rcid,
    REFIID    riid,
    PVOID*    ppv )
```

Parameter

Parameter	Dir.	Description
<i>rcid</i>	[in]	Reference to class ID of the component to be opened. CLSID_VCIBAL: Opens access to Bus Access Layer (BAL).
<i>riid</i>	[in]	Reference to the ID of the interface to access the component.
<i>ppv</i>	[out]	Address of a pointer variable. If run successfully the pointer is stored in the in <i>riid</i> requested interface of the <i>rcid</i> specified component. In case of an error the variable is set to NULL.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

For parameters *rcid* and *riid* the following combinations are possible:

rcid: CLSID_VCIBAL

riid: IID_IUnknown, IID_IBalObject.

For further information about the BAL and its components see [Accessing the Bus Controller, p. 20](#). Observe, that the VCI specific GUIDs must be initialized (see [Using the VCI Headers, p. 8](#) for further information).

7.4 Interfaces of the Communication Components

7.4.1 Interfaces for FIFOs

IVciFifo

Common interface for all FIFO components. Detailed description of FIFO and functionality see [First In/First Out Memory \(FIFO\), p. 13](#). The ID of the interface is IID_IVciFifo.

GetCapacity

Determines the capacity of the FIFO.

```
HRESULT GetCapacity ( PUINT16 pwCapacity );
```

Parameter

Parameter	Dir.	Description
<i>pwCapacity</i>	[out]	Pointer to variable to which the capacity of the FIFO is returned if the function succeeded.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

Function returns the number of data elements that can be stored in the FIFO, not the number of bytes. The size of an individual data element can be determined with the function GetEntrySize.

GetEntrySize

Determines the size of an individual data element in the FIFO in bytes.

```
HRESULT GetEntrySize ( PUINT16 pwSize );
```

Parameter

Parameter	Dir.	Description
<i>pwSize</i>	[out]	Pointer to variable to which the size of an individual data element is returned if the function succeeded.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

GetFreeCount

Determines the current number of free data elements in the FIFO.

```
HRESULT GetFreeCount ( PUINT16 pwCount );
```

Parameter

Parameter	Dir.	Description
<i>pwCount</i>	[out]	Pointer to variable to which the number of free data elements is returned if the function succeeded. Value informs how many data elements additionally fit into the FIFO.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

GetFillCount

Determines the current number of occupied data elements in the FIFO.

```
HRESULT GetFillCount ( PUINT16 pwCount );
```

Parameter

Parameter	Dir.	Description
<i>pwCount</i>	[out]	Pointer to variable to which the number of occupied data elements is returned if the function succeeded. Value informs how many data elements are not yet read.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

GetFillLevel

Determines the filling level of the FIFO in percentage.

```
HRESULT GetFillLevel ( PUINT16 pwLevel );
```

Parameter

Parameter	Dir.	Description
<i>pwLevel</i>	[out]	Pointer to variable to which the current filling level in percentage is returned if the function succeeded.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

IVciFifo2

The interface `IVciFifo2` expands the interface `IVciFifo` with additional features. The ID of the interface is `IID_IVciFifo2`.

Reset

Deletes the current FIFO content.

```
HRESULT Reset ( void );
```

Return Value

Return value	Description
<code>VCI_OK</code>	Function succeeded
<code>!=VCI_OK</code>	Error
<code>VCI_E_ACCESSDENIED</code>	An interface is opened.

Remark

The function is only ran successfully if the FIFO is neither accessed reading nor writing during the function is called. When the function is called neither interface `IFifoReader` nor `IFifoWriter` must be opened.

IFifoReader

The interface is used for the reading access to FIFOs (description see [Functionality of the Receiving FIFO, p. 16](#)). The ID of the interface is `IID_IFifoReader`.

Lock

Waits until the calling thread has exclusive access to the interface and then locks the access to the interface for all other threads of the application.

```
HRESULT Lock ( void );
```

Return Value

Return value	Description
<code>VCI_OK</code>	—

Remark

Applications that access the interface simultaneously from several threads must synchronize the access. For that at the beginning of a reading sequence `Lock` is always called and at the end `Unlock`. The functions `GetCapacity` and `GetEntrySize` are excluded because the values returned by this functions are unchangeable. Multiple overlapping calls of `Lock` and `Unlock` are possible. Make sure that after every call of `Lock` a call of `Unlock` follows.

Unlock

Releases the access to the interface that is locked with [Lock](#).

```
HRESULT Unlock ( void );
```

Return Value

Return value	Description
VCI_OK	—

Remark

For further information see [Lock](#).

AssignEvent

Assigns an *Event* to the FIFO which is always set in signalized state if the filling level of the FIFO exceeds a certain threshold.

```
HRESULT AssignEvent ( HANDLE hEvent );
```

Parameter

Parameter	Dir.	Description
<i>hEvent</i>	[in]	Handle of object. Specified handle must originate of Windows function CreateEvent.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

Exclusively one *Event* can be assigned to the interface. If the function is multiply called a previously assigned *Event* is overwritten. The currently assigned *Event* can be removed by calling the function with value NULL in parameter *hEvent*. The *Event* is triggered if an element is assigned to the FIFO and the filling level reaches or exceeds the set threshold. For further information about the function see [Functionality of the Receiving FIFO, p. 16](#).

SetThreshold

Determines the threshold for the filling level at which the currently assigned *Event* is signalized.

```
HRESULT SetThreshold ( UINT16 wThreshold );
```

Parameter

Parameter	Dir.	Description
<i>wThreshold</i>	[in]	Threshold at which the currently with AssignEvent assigned <i>Event</i> is signalized.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

If the value specified in parameter *wThreshold* exceeds the valid area the function automatically limits the threshold to the capacity of the FIFO. The currently assigned *Event* is triggered if a data element is stored in the FIFO and reaches or exceeds the threshold specified in parameter *wThreshold*. For further information see [Functionality of the Receiving FIFO, p. 16](#).

GetThreshold

Determines the specified threshold at which a currently assigned *Event* is signalized.

```
HRESULT GetThreshold ( PUINT16 pwThreshold );
```

Parameter

Parameter	Dir.	Description
<i>pwThreshold</i>	[out]	Pointer to variable to which the currently assigned threshold is returned if the function succeeded.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

For further information see [SetThreshold](#).

GetCapacity

Determines the capacity of the FIFO.

```
HRESULT GetCapacity ( PUINT16 pwCapacity );
```

Parameter

Parameter	Dir.	Description
<i>pwCapacity</i>	[out]	Pointer to variable to which the capacity of the FIFO is returned if the function succeeded.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

The function returns the number of data elements that can be stored in the FIFO, not the number of bytes. The size of an individual data element can be determined with the function *GetEntrySize*.

GetEntrySize

Determines the size of an individual data element in the FIFO in bytes.

```
HRESULT GetEntrySize ( PUINT16 pwSize );
```

Parameter

Parameter	Dir.	Description
<i>pwSize</i>	[out]	Pointer to variable to which the size of an individual data element is returned if the function succeeded.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function <code>VciFormatError</code>

GetFillCount

Determines the current number of not yet read resp. valid data elements in the FIFO.

```
HRESULT GetFillCount ( PUINT16 pwCount );
```

Parameter

Parameter	Dir.	Description
<i>pwCount</i>	[out]	Pointer to variable to which the current number of occupied data elements is returned if the function succeeded. Value informs how many data elements are not yet read.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function <code>VciFormatError</code>

GetFreeCount

Determines the current number of free data elements in the FIFO.

```
HRESULT GetFreeCount ( PUINT16 pwCount );
```

Parameter

Parameter	Dir.	Description
<i>pwCount</i>	[out]	Pointer to variable to which the number of free data elements is returned if the function succeeded. Value informs how many data elements additionally fit into the FIFO.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

The value that is returned in *pwCount* informs how many additional elements fit into the FIFO until it is crowded.

GetDataEntry

Reads the next valid data element in the FIFO.

```
HRESULT GetDataEntry ( PVOID pvData );
```

Parameter

Parameter	Dir.	Description
<i>pvData</i>	[out]	Pointer to the buffer memory of the data element to be read. If the value NULL is entered the function removes the next element in the FIFO.

Return Value

Return value	Description
VCI_OK	Function succeeded
VCI_E_RXQUEUE_EMPTY	No data element in FIFO while calling the function
!=VCI_OK	Error, further information about error code provides the function <i>VciFormatError</i>

Remark

The function copies the content of the next valid data element to the memory area to which parameter *pvData* is pointing. Because of that the memory area must be at least as big as a data element in the FIFO. The size of an individual data element can be determined with function [GetEntrySize](#).

AcquireRead

Determines a pointer to the next unread data element in the FIFO and the number of elements that can be read sequentially from this position onward.

```
HRESULT AcquireRead (PVOID* ppvData, PUINT16 pwCount );
```

Parameter

Parameter	Dir.	Description
<i>ppvData</i>	[out]	Address of a pointer variable. If run successfully address of first valid element that can be read is stored.
<i>pwCount</i>	[out]	If run successfully pointer to variable in which number of valid elements is stored that can be read from the in <i>ppvData</i> returned address onward.

Return Value

Return value	Description
VCI_OK	Function succeeded
VCI_E_INVALIDARG	Invalid parameter
VCI_E_RXQUEUE_EMPTY	FIFO contains no more valid elements.

Remark

In *ppvData* returned address can be used as pointer to an array with *pwCount* elements. Every element in the array has the size that is specified in bytes when creating the FIFO. Since the pointer returned in *ppvData* points directly to the memory of the FIFO it must be made sure that no element outside the valid area is read.

In parameter *pwCount* the value **NULL** can be specified if the program is only interested in the next free element. In this case when calling [ReleaseRead](#) it is maximally allowed to specify parameter *wCount* with 1.

ReleaseRead

Releases a certain number of data element from the current reading position in the FIFO onward.

```
HRESULT ReleaseRead ( UINT16 wCount );
```

Parameter

Parameter	Dir.	Description
wCount	[in]	Number of data elements in the FIFO to be released

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

The function updates the reading position in the FIFO corresponding to the number of elements specified in *wCount*. The value that is specified in *wCount* must not exceed the number returned by [AcquireRead](#) but can be 0 if no element is to be released.

IFifoWriter

The interface is used for the transmitting access to FIFOs (further information see [Functionality of the Transmitting FIFO, p. 18](#)). The ID of the interface is `IID_IFifoWriter`.

Lock

Waits until the calling thread has exclusive access to the interface and then locks the access to the interface for all other threads of the application.

```
HRESULT Lock ( void );
```

Return Value

Return value	Description
VCI_OK	—

Remark

Applications that access the interface simultaneously from several threads must synchronize the access. For that at the beginning of a writing sequence `Lock` is always called and at the end `Unlock`. The functions `GetCapacity` and `GetEntrySize` are excluded because the values returned by this functions are unchangeable. Multiple overlapping calls of `Lock` and `Unlock` are possible. Make sure that after every call of `Lock` a call of `Unlock` follows.

Unlock

Releases the access to the interface that was locked with `Lock`.

```
HRESULT Unlock ( void );
```

Return Value

Return value	Description
VCI_OK	—

Remark

For further information see function [Lock](#).

AssignEvent

Assigns an *Event* to the FIFO which is always set in signalized state if the number of free elements exceed a certain value or if the filling level is below a certain value.

```
HRESULT AssignEvent ( HANDLE hEvent );
```

Parameter

Parameter	Dir.	Description
<code>hEvent</code>	[in]	Handle of event. Specified handle must originate of Windows API function <code>CreateEvent</code> .

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

Exclusively one *Event* can be assigned to the interface. If the function is multiply called a previously assigned *Event* is overwritten. The currently assigned *Event* can be removed by calling the function with value NULL in parameter *hEvent*. The *Event* is triggered if an element is removed from the FIFO and the specified threshold is reached or exceeded or if the filling level is below a specified value. For further information see [Functionality of the Transmitting FIFO, p. 18.](#)

SetThreshold

Determines the threshold for the filling level at which the currently assigned *Event* is signalized.

```
HRESULT SetThreshold ( UINT16 wThreshold );
```

Parameter

Parameter	Dir.	Description
<i>wThreshold</i>	[in]	Threshold at which the currently with AssignEvent assigned <i>Event</i> is signalized.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

If the value specified in parameter *wThreshold* exceeds the valid area the function automatically limits the threshold to the capacity of the FIFO. The currently assigned *Event* is triggered if an element is removed from the FIFO and the number of free entries reaches or exceeds the threshold specified in parameter *wThreshold* or if the filling level is below a specified value. For further information see [Functionality of the Receiving FIFO, p. 16.](#)

GetThreshold

Determines the specified threshold at which a currently assigned *Event* is signalized.

```
HRESULT GetThreshold ( PUINT16 pwThreshold );
```

Parameter

Parameter	Dir.	Description
<i>pwThreshold</i>	[out]	Pointer to variable to which the currently assigned threshold is returned if the function succeeded.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

For further information see [SetThreshold](#).

GetCapacity

Determines the capacity of the FIFO.

```
HRESULT GetCapacity ( PUINT16 pwCapacity );
```

Parameter

Parameter	Dir.	Description
<i>pwCapacity</i>	[out]	Pointer to variable to which the capacity of the FIFO is returned if the function succeeded.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

The function returns the number of data elements that can be stored in the FIFO, not the number of bytes. The size of an individual data element can be determined with function [GetEntrySize](#).

GetEntrySize

Determines the size of an individual data element in the FIFO in bytes.

```
HRESULT GetEntrySize ( PUINT16 pwSize );
```

Parameter

Parameter	Dir.	Description
<i>pwSize</i>	[out]	Pointer to variable to which the size of an individual data element is returned if the function succeeded.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

GetFillCount

Determines the current number of not yet read resp. valid data elements in the FIFO.

```
HRESULT GetFillCount ( PUINT16 pwCount );
```

Parameter

Parameter	Dir.	Description
<i>pwCount</i>	[out]	Pointer to variable to which the current number of occupied data elements is returned if the function succeeded. Value informs how many data elements are not yet read.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

GetFreeCount

Determines the current number of free data elements in the FIFO.

```
HRESULT GetFreeCount ( PUINT16 pwCount );
```

Parameter

Parameter	Dir.	Description
<i>pwCount</i>	[out]	Pointer to variable to which the number of free data elements is returned if the function succeeded. Value informs how many data elements additionally fit into the FIFO.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

The value returned in *pwCount* informs how many additionally elements fit into the FIFO until it is crowded.

PutDataEntry

Writes a data element to the FIFO.

```
HRESULT PutDataEntry ( PVOID pvData );
```

Parameter

Parameter	Dir.	Description
<i>pvData</i>	[in]	Pointer to the data element to be written

Return Value

Return value	Description
VCI_OK	Function succeeded
VCI_E_TXQUEUE_FULL	No space available in FIFO.
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

The function copies the content of the memory area to which parameter *pvData* is pointing to next valid data element. Because of that the memory area specified in *pvData* must be at least as big as a data element in the FIFO. The size of a data element can be determined with the function [GetEntrySize](#).

AcquireWrite

Determines a pointer to the next unread data element in the FIFO and the number of elements that can be addressed linearly from this position onward.

```
HRESULT AcquireWrite ( PVOID* ppvData, PUINT16 pwCount );
```

Parameter

Parameter	Dir.	Description
<i>ppvData</i>	[out]	Address of a pointer variable. If run successfully address of first valid element that can be addressed is stored.
<i>pwCount</i>	[out]	If run successfully pointer to variable in which number of valid elements is stored that can be addressed from the in <i>ppvData</i> returned address onward.

Return Value

Return value	Description
VCI_OK	Function succeeded
VCI_E_INVALIDARG	Invalid parameter
VCI_E_TXQUEUE_FULL	FIFO contains no more valid elements.

Remark

In *ppvData* returned address can be used as pointer to an array with *pwCount* elements. Every element in the array has the size that is specified in bytes when creating the FIFO. Since the pointer that is returned in *ppvData* points directly to the memory of the FIFO, it must be made sure that no element outside the valid area is addressed. In parameter *pwCount* the value NULL can be specified if the program is only interested in the next free element. In this case when calling [ReleaseRead](#) it is maximally allowed to specify parameter *wCount* with 1.

ReleaseWrite

Releases a certain number of data element from the current reading position in the FIFO onward.

```
HRESULT ReleaseWrite ( UINT16 wCount );
```

Parameter

Parameter	Dir.	Description
<i>wCount</i>	[in]	Number of data element to be declared valid in the FIFO

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

The function updates the writing position in the FIFO corresponding to the number of elements specified in *wCount*. The value that is specified in *wCount* must not exceed the number returned by [AcquireWrite](#) but can be 0 if no element is to be declared valid.

7.5 BAL Specific Interfaces

The following chapters describe the interfaces and functions for the access of the controllers of a bus adapter. Introducing information see [Accessing the Bus Controller, p. 20](#).

7.5.1 IBalObject

The interface provides functions to determine the features of the BAL and to open bus controllers. The ID of the interface is `IID_IBalObject`.

GetFeatures

Determines the functions of the Bus Access Layer (BAL) of the bus adapter.

```
HRESULT GetFeatures ( PBALFEATURES pBalFeatures );
```

Parameter

Parameter	Dir.	Description
<code>pBalFeatures</code>	[out]	Pointer to data block of type <code>BALFEATURES</code> . If run successfully the function stores the features of the BAL in this memory area.

Return Value

Return value	Description
<code>VCI_OK</code>	Function succeeded
<code>!=VCI_OK</code>	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

For further information about the data that are returned by this function see description of the data structure [`BALFEATURES`](#).

OpenSocket

Opens a bus controller and request an interface from it.

```
HRESULT OpenSocket ( UINT32 dwBusNo, REFIID riid, PVOID* ppv );
```

Parameter

Parameter	Dir.	Description
<i>dwBusNo</i>	[in]	Number of the bus controller to be opened. Value 0 selects the first bus controller, value 1 the second, etc.
<i>riid</i>	[in]	Reference to the ID of the interface to access the bus component.
<i>ppv</i>	[out]	Address of a pointer variable. If run successfully the pointer is stored in the in <i>riid</i> requested interface. In case of an error the variable is set to NULL.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

If run successfully the function increments the reference counter of the opened bus controller automatically by 1. When the application do not need the interfaces resp. the bus controller any more, the pointer returned in *ppv* must be released with [Release](#). For information about number and type of available bus controllers and possible values for *dwBusNo* see description of the data structure [BALFEATURES](#).

7.6 CAN Specific Interfaces

7.6.1 ICanSocket

The interface contains functions to request for features and to create message channels for a CAN controller. The ID of the interface is `IID_ICanSocket`.

GetSocketInfo

Determines general information about the bus controller.

```
HRESULT GetSocketInfo ( PBALSOCKETINFO pSocketInfo );
```

Parameter

Parameter	Dir.	Description
<code>pSocketInfo</code>	[out]	Pointer to memory area of type <code>BALSOCKETINFO</code> . If run successfully the function stores the information about the bus controller in this memory area.

Return Value

Return value	Description
<code>VCI_OK</code>	Function succeeded
<code>!=VCI_OK</code>	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

For further information about the data that are returned by this function see description of the data structure `BALSOCKETINFO`.

GetCapabilities

Determines the features of the CAN controller.

```
HRESULT GetCapabilities ( PCANCAPABILITIES pCanCaps );
```

Parameter

Parameter	Dir.	Description
<code>pCanCaps</code>	[out]	Pointer to memory area of type <code>CANCAPABILITIES</code> . If run successfully the function stores the features of the CAN controller in this memory area.

Return Value

Return value	Description
<code>VCI_OK</code>	Function succeeded
<code>!=VCI_OK</code>	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

For further information about the data that are returned by this function see description of the data structure `CANCAPABILITIES`.

GetLineStatus

Determines the current settings and the current state of the CAN Controller.

```
HRESULT GetLineStatus ( PCANLINESTATUS pLineStatus );
```

Parameter

Parameter	Dir.	Description
<i>pLineStatus</i>	[out]	Pointer to memory area of type CANLINESTATUS. If run successfully the function saves the current settings and the current state of the controller in this memory area.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

For further information about the data that are returned by this function see description of the data structure [CANLINESTATUS](#).

CreateChannel

Opens resp. creates a message channel for the CAN controller.

```
HRESULT CreateChannel (
    BOOL          fExclusive,
    PCANCHANNEL*  ppChannel );
```

Parameter

Parameter	Dir.	Description
<i>fExclusive</i>	[in]	Determines if the controller is exclusively used for the channel to be opened. If the value TRUE is specified no further message channels can be opened after the function ran successfully until the newly generated channel is released again. If value FALSE is specified multiple message channels for the CAN controller can be opened.
<i>ppChannel</i>	[out]	Address of a variable to which a pointer to the interface ICanChannel is assigned by the newly generated message channel if ran successfully. In case of an error the variable is set to NULL.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

The program that calls the function first with the value TRUE in parameter *fExclusive* exclusively controls the message transfer on the CAN bus. If the message channel is not required any more the pointer returned in *ppChannel* must be released by calling the function [Release](#). For general information about message channels see [Message Channels, p. 23](#).

7.6.2 ICanSocket2

The interface contains functions to request for the features and to create message channels for a expanded CAN controller. The ID of the interface is IID_ICanSocket2.

GetSocketInfo

Determines general information about the bus controller.

```
HRESULT GetSocketInfo ( PBALSOCKETINFO pSocketInfo );
```

Parameter

Parameter	Dir.	Description
pSocketInfo	[out]	Pointer to memory area of type BALSOCKETINFO. If run successfully the function stores the information about the bus controller in this memory area.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

For further information about the data that are returned by this function see description of the data structure [BALSOCKETINFO](#).

GetCapabilities

Determines the features of the CAN controller.

```
HRESULT GetCapabilities ( PCANCAPABILITIES pCanCaps );
```

Parameter

Parameter	Dir.	Description
pCanCaps	[out]	Pointer to memory area of type CANCAPABILITIES2. If run successfully the function stores the features of the CAN controller in this memory area.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

For further information about the data that are returned by this function see description of the data structure [CANCAPABILITIES2](#).

GetLineStatus

Determines the current settings and the current state of the CAN Controller.

```
HRESULT GetLineStatus ( PCANLINESTATUS2 pLineStatus );
```

Parameter

Parameter	Dir.	Description
<i>pLineStatus</i>	[out]	Pointer to memory area of type CANLINESTATUS2. If run successfully the function saves the current settings and the current state of the controller in this memory area.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

For further information about the data that are returned by this function see description of the data structure [CANLINESTATUS2](#).

CreateChannel

Opens resp. creates a message channel for the CAN controller.

```
HRESULT CreateChannel (
    BOOL          fExclusive,
    PCANCHANNEL2* ppChannel );
```

Parameter

Parameter	Dir.	Description
<i>fExclusive</i>	[in]	Determines if the controller is exclusively used for the channel to be opened. If the value TRUE is specified no further message channels can be opened after the function ran successfully until the newly generated channel is released again. If value FALSE is specified multiple message channels for the CAN controller can be opened.
<i>ppChannel</i>	[out]	Address of a variable to which a pointer to the interface ICanChannel2 is assigned by the newly generated message channel if ran successfully. In case of an error the variable is set to NULL.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

The program that calls the function first with the value TRUE in parameter *fExclusive* exclusively controls the message transfer on the CAN bus. If the message channel is not required any more the pointer that is returned in *ppChannel* must be released by calling the function [Release](#). For general information about message channels see [Message Channels, p. 23](#).

7.6.3 ICanControl

Basic information to the functionality of the component see [Control Unit, p. 33](#). The ID of the interface is IID_ICanControl.

DetectBaud

Determines the current bit rate of the CAN bus connected to the adapter.

```
HRESULT DetectBaud (
    UINT16          wTimeoutMs,
    PCANBTRTABLE  pBtrTable );
```

Parameter

Parameter	Dir.	Description
wTimeoutMs	[in]	Maximum waiting time in milliseconds between two receiving messages on the bus.
pBtrTable	[in/out]	Pointer to a initialized structure of type CANBTRTABLE with predefined set of bus timing values to be tested.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError
VCI_E_NOT_IMPLEMENTED	Function not supported by device
VCI_E_TIMEOUT	No communication on the bus during the time specified in wTimeoutMs

Remark

If run successfully, field *bIndex* of structure [CANBTRTABLE](#) contains the table index of the found bus timing values. The values at the respective positions in the tables *abBtr0* and *abBtr1* can then be used to initialize the CAN controller with [InitLine](#).

Before calling it is possible to specify in *bIndex* additional parameters about the operating mode that is used by the bit rate to detect. Valid is either [CAN_OPMODE_LOWSPEED](#) or 0, if no low speed coupling is desired. The function can be called in undefined state or after a reset of the controller. Further information about the automatic detection of the bit rate see [Determine the Bit Rate Used in the Network, p. 40](#).

InitLine

Specifies the operating mode and the bit rate of the CAN controller.

```
HRESULT InitLine ( PCANINITLINE pInitParam );
```

Parameter

Parameter	Dir.	Description
<i>pInitParam</i>	[in]	Pointer to initialized structure of type CANINITLINE. Field <i>bOpMode</i> determines the operating mode, Fields <i>bBtReg0</i> and <i>bBtReg1</i> the bit rate of the CAN controller. For further information about the fields see description of the data structure CANINITLINE .

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

The function resets the controller hardware like the function [ResetLine](#). The controller is newly initialized with the specified values. For values for the bus timing register BTR0 and BTR1 resp. the therefore defined constants for the CiA resp. CANopen specified bit rates and further information about setting the bit rate see [Specifying the Bit Rate, p. 35](#).

ResetLine

Resets the CAN controller and the message filters of the control unit to the initial state.

```
HRESULT ResetLine ( void );
```

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

For further information see [Stopping \(resp. Reset\) the Controller, p. 34](#).

StartLine

Starts the CAN controller.

```
HRESULT StartLine ( void );
```

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

For further information see [Control Unit, p. 33](#).

StopLine

Stops the CAN controller.

```
HRESULT StopLine ( void );
```

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

Unlike [ResetLine](#) the specified message filters are not modified when the controller is stopped. For further information see [Control Unit, p. 33](#).

GetLineStatus

Determines the current settings and the current state of the CAN Controller.

```
HRESULT GetLineStatus ( PCANLINESTATUS pLineStatus );
```

Parameter

Parameter	Dir.	Description
pLineStatus	[out]	Pointer to memory area of type CANLINESTATUS. If run successfully the function saves the current settings and the current state of the controller in this memory area.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

The function can always be called, even before the first call of one of the functions [InitLine](#) or [DetectBaud](#). For further information about the data that are returned by this function see description of the data structure [CANLINESTATUS](#).

SetAccFilter

Specifies an acceptance filter of the CAN controller.

```
HRESULT SetAccFilter (
    UINT8 bSelect,
    UINT32 dwCode,
    UINT32 dwMask );
```

Parameter

Parameter	Dir.	Description
bSelect	[in]	Selects the acceptance filter. With CAN_FILTER_STD the 11 bit, with CAN_FILTER_EXT the 29 bit filter is selected.
dwCode	[in]	Bit sample of the CAN identifiers to be accepted including RTR bit.
dwMask	[in]	Bit samples of the relevant bits in dwCode. If a bit in dwMask has the value 0 the correlating bit in dwCode is not used for the comparison. But if it has the value 1 it is relevant for the comparison.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

For detailed description of the functionality of the filter and the values for the parameter dwCode and dwMask see [Message Filter, p. 42](#).

AddFilterIds

Assigns one or more CAN message IDs (CAN-ID) in the 11 or 29 bit filter list of the CAN controller.

```
HRESULT AddFilterIds (
    UINT8 bSelect,
    UINT32 dwCode,
    UINT32 dwMask );
```

Parameter

Parameter	Dir.	Description
bSelect	[in]	Selects the acceptance filter. With CAN_FILTER_STD the 11 bit, with CAN_FILTER_EXT the 29 bit filter is selected.
dwCode	[in]	Bit sample of the CAN identifiers to be registered including RTR bit.
dwMask	[in]	Bit samples of the relevant bits in dwCode. If a bit in dwMask has the value 0 the correlating bit in dwCode is not considered. But if it has the value 1 it is relevant.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

For detailed description of the functionality of the filter and the values for the parameter dwCode and dwMask see [Message Filter, p. 42](#).

RemFilterIds

Removes one or more CAN message IDs (CAN-ID) from the 11 or 29 bit filter list of the CAN controller.

```
HRESULT RemFilterIds (
    UINT8 bSelect,
    UINT32 dwCode,
    UINT32 dwMask );
```

Parameter

Parameter	Dir.	Description
<i>bSelect</i>	[in]	Selects the acceptance filter. With CAN_FILTER_STD the 11 bit, with CAN_FILTER_EXT the 29 bit filter is selected.
<i>dwCode</i>	[in]	Bit samples of the CAN identifiers to be removed including RTR bit.
<i>dwMask</i>	[in]	Bit samples of the relevant bits in <i>dwCode</i> . If a bit in <i>dwMask</i> has the value 0 the correlating bit in <i>dwCode</i> is not considered. But if it has the value 1 it is relevant.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

For detailed description of the functionality of the filter and the values for the parameter *dwCode* and *dwMask* see [Message Filter, p. 42](#).

7.6.4 ICanControl2

Basic information to the functionality of the component see [Control Unit, p. 33](#). The ID of the interface is IID_ICanControl2.

DetectBaud

Determines the current bit rate of the CAN bus connected to the adapter.

```
HRESULT DetectBaud (
    UINT8      bOpMode
    UINT8      bExMode
    UINT16     wTimeoutMs,
    PCANBTPTABLE pBtpTable );
```

Parameter

Parameter	Dir.	Description
<i>bOpMode</i>	[in]	Operating mode of the controller used for detection. CAN_OPMODE_LOWSPEED: CAN controller uses low speed bus coupling.
<i>bExMode</i>	[in]	Extended operating mode of the controller used for detection. If supported by the controller, a logical combination of one or more of the following constants can be specified: CAN_EXMODE_FASTDATA: Allows higher bit rates for the data field CAN_EXMODE_NONISO: Use of non-ISO-conform message frames. This option is exclusively available with older CAN FD controller with the feature CAN_FEATURE_NONISOFRM. If the value CAN_EXMODE_DISABLED is specified there is no detection of the fast bit rates. The value also must be specified with all other controllers that do not support extended CAN FD operating mode. See description of field <i>dwFeatures</i> of structure CANCAPABILITIES2 .
<i>wTimeoutMs</i>	[in]	Maximum waiting time in milliseconds between two receiving messages on the bus.
<i>pBtpTable</i>	[in/out]	Pointer to a initialized structure of type CANBTPTABLE with preset bus timing values to be tested.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError
VCI_E_NOT_IMPLEMENTED	Function not supported by device
VCI_E_TIMEOUT	No communication on the bus during the specified time

Remark

If run successfully, field *bIndex* of structure [CANBTPTABLE](#) contains the table index of the found bus timing values. The values at the respective positions in the table can then be used to initialize the CAN controller with [InitLine](#). The function can be called in undefined state or after a reset of the controller. For further information about the automatic detection of the bit rate see [Determine the Bit Rate Used in the Network, p. 40](#).

InitLine

Specifies the operating mode and bit rate of the CAN controller and the default and reset values of the operating mode of the message filters.

```
HRESULT InitLine ( PCANINITLINE2 pInitParam );
```

Parameter

Parameter	Dir.	Description
<i>pInitParam</i>	[in]	Pointer to structure of type CANINITLINE2 with the parameters required for configuration of operating mode, bit rate and message filters. For further information about the fields see description of the data structure CANINITLINE2 .

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

The function resets the controller hardware like the function [ResetLine](#). The controller is initialized with specified values. For further information about setting the bit rate see [Specifying the Bit Rate, p. 35](#).

ResetLine

Resets the CAN controller and the message filters of the control unit to the initial state.

```
HRESULT ResetLine ( void );
```

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

For further information see [Stopping \(resp. Reset\) the Controller, p. 34](#).

StartLine

Starts the CAN controller.

```
HRESULT StartLine ( void );
```

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

For further information see [Starting the Controller, p. 34](#).

StopLine

Stops the CAN controller.

```
HRESULT StopLine ( void );
```

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

Unlike ResetLine the specified message filters are not modified when the controller is stopped. For further information see [Control Unit, p. 33](#).

GetLineStatus

Determines the current settings and the current state of the CAN Controller.

```
HRESULT GetLineStatus ( PCANLINESTATUS2 pLineStatus );
```

Parameter

Parameter	Dir.	Description
pLineStatus	[out]	Pointer to memory area of type CANLINESTATUS2 . If run successfully the function saves the current settings and the current state of the controller in this memory area.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

The function can always be called, even before the first call of one of the functions InitLine or DetectBaud. For further information about the data that are returned by this function see description of the data structure [CANLINESTATUS2](#).

GetFilterMode

Determines the current operating mode of the message filter of the control unit.

```
HRESULT GetFilterMode (
    UINT8 bSelect,
    PUINT8 pbMode );
```

Parameter

Parameter	Dir.	Description
bSelect	[in]	Selecting the filter. With CAN_FILTER_STD the 11 bit, with CAN_FILTER_EXT the 29 bit filter is selected.
pbMode	[out]	Pointer to variable of type UINT8. If run successfully the value of the currently specified operating mode is assigned. Further information about the returned value see description of function SetFilterMode.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

For detailed description of functionality of message filter see [Message Filter, p. 42.](#)

SetFilterMode

Specifies the operating mode of the message filter of the control unit.

```
HRESULT SetFilterMode (
    UINT8 bSelect,
    UINT8 bNewMode,
    PUINT8 pbPrevMode );
```

Parameter

Parameter	Dir.	Description
bSelect	[in]	Selecting the filter. With CAN_FILTER_STD the 11 bit, with CAN_FILTER_EXT the 29 bit filter is selected.
bNewMode	[in]	Parameter determines new operating mode for selected filter. One of the following constants can be specified: CAN_FILTER_LOCK: Filter blocks all messages of type CAN_MSGTYPE_DATA, independent of the ID. The other message types like for example CAN_MSGTYPE_INFO are not concerned and can always pass. CAN_FILTER_PASS: Filter is completely opened and all data messages can pass. CAN_FILTER_INCL: All data messages of type CAN_MSGTYPE_DATA with an ID either released in the acceptance filter or registered in the filter list can pass the filter (e. i. all registered IDs). Other message types are not concerned and can always pass. CAN_FILTER_EXCL: All data messages of type CAN_MSGTYPE_DATA with an ID either released in the acceptance filter or registered in the filter list are blocked by the filter (e. i. all registered IDs). Other message types are not concerned and can always pass.
pbPrevMode	[out]	Pointer to variable of type UINT8. If run successfully the value of the last specified operating mode is assigned. The parameter is optional and can be set to NULL if the value is not required.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

For detailed description of FIFO and functionality see [Message Filter, p. 42.](#)

SetAccFilter

Specifies an acceptance filter of the CAN controller.

```
HRESULT SetAccFilter (
    UINT8 bSelect,
    UINT32 dwCode,
    UINT32 dwMask );
```

Parameter

Parameter	Dir.	Description
bSelect	[in]	Selects the acceptance filter. With CAN_FILTER_STD the 11 bit, with CAN_FILTER_EXT the 29 bit filter is selected.
dwCode	[in]	Bit sample of the CAN identifiers to be accepted including RTR bit.
dwMask	[in]	Bit samples of the relevant bits in dwCode. If a bit in dwMask has the value 0 the correlating bit in dwCode is not used for the comparison. But if it has the value 1 it is relevant for the comparison.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

For detailed description of the functionality of the filter and the values for the parameter dwCode and dwMask see [Message Filter, p. 42](#).

AddFilterIds

Assigns one or more CAN message IDs (CAN-ID) in the 11 or 29 bit filter list of the control unit.

```
HRESULT AddFilterIds (
    UINT8 bSelect,
    UINT32 dwCode,
    UINT32 dwMask );
```

Parameter

Parameter	Dir.	Description
bSelect	[in]	Selects the acceptance filter. With CAN_FILTER_STD the 11 bit, with CAN_FILTER_EXT the 29 bit filter is selected.
dwCode	[in]	Bit sample of the identifiers to be registered including RTR bit.
dwMask	[in]	Bit samples of the relevant bits in dwCode. If a bit in dwMask has the value 0 the correlating bit in dwCode is not considered. But if it has the value 1 it is relevant.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

For detailed description of the functionality of the filter and the values for the parameter dwCode and dwMask see [Message Filter, p. 42](#).

RemFilterIds

Removes one or more CAN message IDs (CAN-ID) from the 11 or 29 bit filter list of the control unit.

```
HRESULT RemFilterIds (
    UINT8 bSelect,
    UINT32 dwCode,
    UINT32 dwMask );
```

Parameter

Parameter	Dir.	Description
<i>bSelect</i>	[in]	Selects the acceptance filter. With CAN_FILTER_STD the 11 bit, with CAN_FILTER_EXT the 29 bit filter is selected.
<i>dwCode</i>	[in]	Bit sample of the identifiers to be removed including RTR bit.
<i>dwMask</i>	[in]	Bit samples of the relevant bits in <i>dwCode</i> . If a bit in <i>dwMask</i> has the value 0 the correlating bit in <i>dwCode</i> is not considered. But if it has the value 1 it is relevant.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

For detailed description of the functionality of the filter and the values for the parameter *dwCode* and *dwMask* see [Message Filter, p. 42](#).

7.6.5 ICanChannel

The interface provides functions to create a message channel. Basic information to the functionality of the component see [Message Channels, p. 23](#). The ID of the interface is `IID_ICanChannel`.

Initialize

Initializes the receiving and the transmitting FIFO of the message channel.

```
HRESULT Initialize ( UINT16 wRxFifoSize, UINT16 wTxFifoSize );
```

Parameter

Parameter	Dir.	Description
<code>wRxFifoSize</code>	[in]	Size of receiving FIFO in number of CAN messages
<code>wTxFifoSize</code>	[in]	Size of transmitting FIFO in number of CAN messages

Return Value

Return value	Description
<code>VCI_OK</code>	Function succeeded
<code>VCI_E_INVALIDARG</code>	Value in parameter <code>wRxFifoSize</code> must be higher than 0.
<code>!=VCI_OK</code>	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

The specified values determine exclusively the lower limit for the size of the respective FIFO. The actual size is eventually bigger as specified, because the memory for the FIFOs is reserved page by page and the pages are always used completely. For further information see [First In/First Out Memory \(FIFO\), p. 13](#). In parameter `wRxFifoSize` a value higher than 0 must be set. Otherwise the function returns an error code. If no transmitting FIFO is needed, for example if the controller is run in *listen-only* mode, value 0 can be set in `wTxFifoSize`.

Activate

Activates the message channel and connects the receiving and the transmitting FIFO to the CAN controller.

```
HRESULT Activate ( void );
```

Return Value

Return value	Description
<code>VCI_OK</code>	Function succeeded
<code>!=VCI_OK</code>	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

By default the message channel is deactivated and disconnected from the bus after it is created resp. initialized. To connect the channel to the bus, the bus must be activated. For further information see [Message Channels, p. 23](#).

Deactivate

Deactivates the message channel and disconnects the receiving and the transmitting FIFO from the CAN controller.

```
HRESULT Deactivate ( void );
```

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

After deactivating the channel no more messages can be transmitted or received.

GetReader

Determines a pointer to the interface `IFifoReader` of the receiving FIFO of the message channel.

```
HRESULT GetReader ( IFifoReader** ppReader );
```

Parameter

Parameter	Dir.	Description
<code>ppReader</code>	[out]	Address of a variable to which a pointer to the interface <code>IFifoReader</code> is assigned by the receiving FIFO if ran successfully. In case of an error the variable is set to <code>NULL</code> .

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

The function succeeds if the channel is initialized with the function [Initialize](#). If the pointer returned by the function is not required any more the pointer must be released with [Release](#).

GetWriter

Determines a pointer to the interface `IFifoWriter` of the transmitting FIFO of the message channel.

```
HRESULT GetWriter ( IFifoWriter** ppWriter );
```

Parameter

Parameter	Dir.	Description
<code>ppWriter</code>	[out]	Address of a variable to which a pointer to the interface <code>IFifoWriter</code> is assigned by the transmitting FIFO if ran successfully. In case of an error the variable is set to <code>NULL</code> .

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

The function succeeds if the channel is initialized with the function `Initialize`. If the pointer returned by the function is not required any more the pointer must be released with `Release`.

GetStatus

Determines the current state of the message channel and the CAN controller that is connected to the message channel.

```
HRESULT GetStatus ( PCANCHANSTATUS pStatus );
```

Parameter

Parameter	Dir.	Description
<i>pStatus</i>	[out]	Pointer to memory area of type <code>CANCHANSTATUS</code> . If run successfully the function saves the current settings and the current state of the message channel in this memory area.

Return Value

Return value	Description
<code>VCI_OK</code>	Function succeeded
<code>!=VCI_OK</code>	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

The function can always be called, even before the first call of one of the function `Initialize`. For further information about the data returned by this function see description of the structure [`CANCHANSTATUS`](#).

7.6.6 ICanChannel2

The interface provides functions to create a message channel. Basic information to the functionality of the component see [Message Channels, p. 23](#). The ID of the interface is `IID_ICanChannel2`.

Initialize

Initializes the receiving and the transmitting FIFO of the message channel.

```
HRESULT Initialize (
    UINT32 dwRxFifoSize,
    UINT32 dwTxFifoSize
    UINT32 dwFilterSize
    UINT8 bFilterMode );
```

Parameter

Parameter	Dir.	Description
<code>dwRxFifoSize</code>	[in]	Size of receiving FIFO in number of CAN messages
<code>dwTxFifoSize</code>	[in]	Size of transmitting FIFO in number of CAN messages
<code>dwFilterSize</code>	[in]	Number of 29 bit message IDs supported by the filter list. 11 bit filter list supports all 2048 possible message IDs. If value 0 is specified, no filter list is created. In this case exact filtering is not possible. Filtering with acceptance filter is not affected by that.
<code>bFilterMode</code>	[in]	Default value for operating mode of message filter. One of the following constants can be specified: <code>CAN_FILTER_LOCK</code> : Filter blocks all messages of type <code>CAN_MSGTYPE_DATA</code> , independent of the ID. The other message types like for example <code>CAN_MSGTYPE_INFO</code> are not concerned and can always pass. <code>CAN_FILTER_PASS</code> : Filter is completely opened and all messages can pass. <code>CAN_FILTER_INCL</code> : All data messages of type <code>CAN_MSGTYPE_DATA</code> with an ID either released in the acceptance filter or registered in the filter list can pass the filter (e. i. all registered IDs). Other message types are not concerned and can always pass. <code>CAN_FILTER_EXCL</code> : All data messages with an ID either released in the acceptance filter or registered in the filter list are blocked by the filter (e. i. all registered IDs). Other message types are not concerned and can always pass. The filter operating mode can be combined with the constant <code>CAN_FILTER_SRRA</code> . The message channel then receives all self reception messages that are transmitted to the controller by other channels. If <code>CAN_FILTER_SRRA</code> is not specified the channel exclusively receives its own self reception messages.

Return Value

Return value	Description
<code>VCI_OK</code>	Function succeeded
<code>!=VCI_OK</code>	Error, further information about error code provides the function <code>VciFormatError</code>
<code>VCI_E_INVALIDARG</code>	Value in parameter <code>dwRxFifoSize</code> must be higher than 0.

Remark

The values that are specified in `dwRxSize` resp. `dwTxSize` determine exclusively the lower limit for the size of the respective FIFO. The actual size is eventually bigger as specified, because the memory for the FIFOs is reserved page by page and the pages are always used completely. For further information see [First In/First Out Memory \(FIFO\), p. 13](#). In parameter `dwRxFifoSize` a value higher than 0 must be set. Otherwise the function returns an error code. If no transmitting FIFO is needed, for example if the controller is run in *listen-only* mode, value 0 can be set in `dwTxFifoSize`.

Activate

Activates the message channel and connects the receiving and the transmitting FIFO to the CAN controller.

```
HRESULT Activate ( void );
```

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

By default the message channel is deactivated and disconnected from the bus after it is created resp. initialized. To connect the channel to the bus, the bus must be activated. For further information see [Message Channels, p. 23](#).

Deactivate

Deactivates the message channel and disconnects the receiving and the transmitting FIFO from the CAN controller.

```
HRESULT Deactivate ( void );
```

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

After deactivating the channel no more messages can be transmitted or received.

GetReader

Determines a pointer to the interface [IFifoReader](#) of the receiving FIFO of the message channel.

```
HRESULT GetReader ( IFifoReader** ppReader );
```

Parameter

Parameter	Dir.	Description
<i>ppReader</i>	[out]	Address of a variable to which a pointer to the interface IFifoReader is assigned by the receiving FIFO if ran successfully. In case of an error the variable is set to <code>NULL</code> .

Return Value

Return value	Description
<code>VCI_OK</code>	Function succeeded
<code>!=VCI_OK</code>	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

The function succeeds if the channel is initialized with the function `Initialize`. If the pointer that is returned by the function is not required any more the pointer must be released with `Release`.

GetWriter

Determines a pointer to the interface [IFifoWriter](#) of the transmitting FIFO of the message channel.

```
HRESULT GetWriter ( IFifoWriter** ppWriter );
```

Parameter

Parameter	Dir.	Description
<i>ppWriter</i>	[out]	Address of a variable to which a pointer to the interface IFifoWriter is assigned by the transmitting FIFO if ran successfully. In case of an error the variable is set to <code>NULL</code> .

Return Value

Return value	Description
<code>VCI_OK</code>	Function succeeded
<code>!=VCI_OK</code>	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

The function succeeds if the channel is initialized with the function `Initialize`. If the pointer that is returned by the function is not required any more the pointer must be released with `Release`.

GetStatus

Determines the current state of the message channel and the CAN controller that is connected to the message channel.

```
HRESULT GetStatus ( PCANCHANSTATUS2 pStatus );
```

Parameter

Parameter	Dir.	Description
<i>pStatus</i>	[out]	Pointer to memory area of type <i>CANCHANSTATUS2</i> . If run successfully the function saves the current settings and the current state of the message channel in this memory area.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function <i>VciFormatError</i>

Remark

The function can always be called, even before the first call of one of the function *Initialize*. For further information about the data returned by this function see description of the structure *CANCHANSTATUS2*.

GetControl

Opens the control unit of the controller that is connected to the message channel.

```
HRESULT GetControl ( PCANCONTROL2* ppCanCtrl );
```

Parameter

Parameter	Dir.	Description
<i>ppCanCtrl</i>	[out]	Address of a variable to which a pointer to the interface <i>ICanControl2</i> is assigned by the opened control unit if run successfully. In case of an error the variable is set to <i>NULL</i> .

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function <i>VciFormatError</i>

Remark

The control unit of a controller can exclusively be opened once at a certain time. If the control unit is not required any more the pointer that is returned in *ppCanCtrl* must be released by calling the function *Release*.

GetFilterMode

Determines the current operating mode of the message channel.

```
HRESULT GetFilterMode (
    UINT8 bSelect,
    PUINT8 pbMode );
```

Parameter

Parameter	Dir.	Description
bSelect	[in]	Selecting the filter. With CAN_FILTER_STD the 11 bit, with CAN_FILTER_EXT the 29 bit filter is selected.
pbMode	[out]	Pointer to variable of type <code>UINT8</code> . If run successfully the value of the currently specified operating mode is assigned. Further information about the returned value see description of function <code>SetFilterMode</code> .

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

For detailed description of functionality of message filter see [Message Filter, p. 42](#).

SetFilterMode

Determines the operating mode of the message channel.

```
HRESULT SetFilterMode (
    UINT8 bSelect,
    UINT8 bNewMode,
    PUINT8 pbPrevMode );
```

Parameter

Parameter	Dir.	Description
bSelect	[in]	Selecting the filter. With value CAN_FILTER_STD the 11 bit and with value CAN_FILTER_EXT the 29 bit filter is selected.
bNewMode	[in]	Parameter determines new operating mode for selected filter. One of the following constants can be specified: CAN_FILTER_LOCK: Filter blocks all messages of type CAN_MSGTYPE_DATA, independent of the ID. The other message types like for example CAN_MSGTYPE_INFO are not concerned and can always pass. CAN_FILTER_PASS: Filter is completely opened and all messages can pass. CAN_FILTER_INCL: All data messages of type CAN_MSGTYPE_DATA with an ID either released in the acceptance filter or registered in the filter list can pass the filter (e. i. all registered IDs). Other message types are not concerned and can always pass. CAN_FILTER_EXCL: All data messages of type CAN_MSGTYPE_DATA with an ID either released in the acceptance filter or registered in the filter list are blocked by the filter (e. i. all registered IDs). Other message types are not concerned and can always pass.
pbPrevMode	[out]	Pointer to variable of type <code>UINT8</code> . If run successfully the value of the last specified operating mode is assigned. The parameter is optional and can be set to <code>NULL</code> if the value is not required.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

For detailed description of functionality of message filter see [Message Filter, p. 42.](#)

SetAccFilter

Specifies the 11 or the 29 bit acceptance filter of the CAN message channel.

```
HRESULT SetAccFilter (
    UINT8 bSelect,
    UINT32 dwCode,
    UINT32 dwMask );
```

Parameter

Parameter	Dir.	Description
<i>bSelect</i>	[in]	Selects the acceptance filter. With CAN_FILTER_STD the 11 bit, with CAN_FILTER_EXT the 29 bit filter is selected.
<i>dwCode</i>	[in]	Bit sample of the CAN identifiers to be accepted including RTR bit.
<i>dwMask</i>	[in]	Bit samples of the relevant bits in <i>dwCode</i> . If a bit in <i>dwMask</i> has the value 0 the correlating bit in <i>dwCode</i> is not used for the comparison. But if it has the value 1 it is relevant for the comparison.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

For detailed description of the functionality of the filter and the values for the parameter *dwCode* and *dwMask* see [Message Filter, p. 42.](#)

AddFilterIds

Assigns one or more CAN message IDs (CAN-ID) in the 11 or 29 bit filter list of the message list.

```
HRESULT AddFilterIds (
    UINT8 bSelect,
    UINT32 dwCode,
    UINT32 dwMask );
```

Parameter

Parameter	Dir.	Description
bSelect	[in]	Selects the acceptance filter. With CAN_FILTER_STD the 11 bit, with CAN_FILTER_EXT the 29 bit filter is selected.
dwCode	[in]	Bit sample of the CAN identifiers to be registered including RTR bit.
dwMask	[in]	Bit samples of the relevant bits in dwCode. If a bit in dwMask has the value 0 the correlating bit in dwCode is not considered. If it has the value 1 it is relevant.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

For detailed description of the functionality of the filter and the values for the parameter dwCode and dwMask see [Message Filter, p. 42](#).

RemFilterIds

Removes one or more CAN message IDs (CAN-ID) from the 11 or 29 bit filter list of the message channel.

```
HRESULT RemFilterIds (
    UINT8 bSelect,
    UINT32 dwCode,
    UINT32 dwMask );
```

Parameter

Parameter	Dir.	Description
bSelect	[in]	Selects the acceptance filter. With CAN_FILTER_STD the 11 bit, with CAN_FILTER_EXT the 29 bit filter is selected.
dwCode	[in]	Bit sample of the CAN identifiers to be removed including RTR bit.
dwMask	[in]	Bit samples of the relevant bits in dwCode. If a bit in dwMask has the value 0 the correlating bit in dwCode is not considered. If it has the value 1 it is relevant.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

For detailed description of the functionality of the filter and the values for the parameter dwCode and dwMask see [Message Filter, p. 42](#).

7.6.7 ICanScheduler

The interface provides functions to create, start and stop the cyclic transmitting list of a CAN controller. Basic information to the functionality of the component see [Cyclic Transmitting List, p. 46](#). The ID of the interface is `IID_ICanScheduler`.

Resume

Starts the transmitting task of the cyclic transmitting list and therefore the transfer of all currently registered transmitting objects.

```
HRESULT Resume ( void );
```

Return Value

Return value	Description
<code>VCI_OK</code>	Function succeeded
<code>!=VCI_OK</code>	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

The function can be used to start all registered transmitting objects simultaneously. Before calling the function all transmitting objects must be set in a started state with the function `StartMessage`. A subsequent call of this function then guarantees a simultaneous start of all registered transmitting objects.

Suspend

Stops the transmitting task of the cyclic transmitting list and therefore the transfer of all currently registered transmitting objects.

```
HRESULT Suspend ( void );
```

Return Value

Return value	Description
<code>VCI_OK</code>	Function succeeded
<code>!=VCI_OK</code>	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

The function stops all transmitting objects simultaneously.

Reset

Stops the transmitting task and removes all transmitting objects from the cyclic transmitting list.

```
HRESULT Reset ( void );
```

Return Value

Return value	Description
<code>VCI_OK</code>	Function succeeded
<code>!=VCI_OK</code>	Error, further information about error code provides the function <code>VciFormatError</code>

GetStatus

Determines the current state of the transmitting task and of all registered transmitting objects of a cyclic transmitting list.

```
HRESULT GetStatus ( PCANSCHEDULERSTATUS pStatus );
```

Parameter

Parameter	Dir.	Description
pStatus	[out]	Pointer to structure of type CANSCHEDULERSTATUS . If run successfully the function saves the current settings and the current state of all cyclic transmitting objects in this memory area.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

The function returns in the array [CANSCHEDULERSTATUS.abMsgStat](#) the state of all transmitting objects. The list index returned by function [AddMessage](#) is used to request the state of a transmitting object, this means the array element [abMsgStat\[Index\]](#) contains the state of the transmitting object of the specified index. For further information about the data that are returned by this function see description of the data structure [CANSCHEDULERSTATUS](#).

AddMessage

Adds a new transmitting object to the cyclic transmitting list.

```
HRESULT AddMessage (
    PCANCYCLICTXMSG pMessage,
    PUINT32          pdwIndex );
```

Parameter

Parameter	Dir.	Description
pMessage	[in]	Pointer to initialized structure of type CANCYCLICTXMSG with the cyclic transmitting object.
pdwIndex	[out]	Pointer to variable of type UINT32 . If successfully executed, the function returns the list index of the newly added transmitting object of this variable. In case of an error the variable is set to 0xFFFFFFFF . This index is required for all further callings of functions.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

The cyclic transmitting of the newly added transmitting object starts after the successful calling of the function [StartMessage](#). The transmitting list must be simultaneously active (see [Resume](#)).

RemMessage

Stops the processing of a transmitting object and removes it from the cyclic transmitting list.

```
HRESULT RemMessage ( UINT32 dwIndex );
```

Parameter

Parameter	Dir.	Description
<i>dwIndex</i>	[in]	List index of the transmitting object to be removed. The list index must originate from an earlier call of the function AddMessage .

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

After calling the function the list index specified in *dwIndex* is invalid and must not be used any more.

StartMessage

Starts the processing of a transmitting object of the cyclic transmitting list.

```
HRESULT StartMessage ( UINT32 dwIndex, UINT16 dwCount );
```

Parameter

Parameter	Dir.	Description
<i>dwIndex</i>	[in]	List index of the transmitting object to be started. The list index must originate from an earlier call of the function AddMessage .
<i>dwCount</i>	[in]	Number of cyclic transmitting repetitions. With value 0 the transmitting is repeated endlessly. The specified value must be in between 0 and 65535.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

The cyclic transmitting exclusively starts if the transmitting task is active when calling the function. If the transmitting task is inactive the transmitting is delayed until the next calling of function [Resume](#).

StopMessage

Stops the processing of a transmitting object of the cyclic transmitting list.

```
HRESULT StopMessage ( UINT32 dwIndex );
```

Parameter

Parameter	Dir.	Description
dwIndex	[in]	List index of the transmitting object to be stopped. The list index must originate from an earlier call of the function AddMessage .

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

7.6.8 ICanScheduler2

The interface provides functions to create, start and stop the cyclic transmitting list of an extended CAN controller. Basic information to the functionality of the component see [Cyclic Transmitting List, p. 46](#). The ID of the interface is IID_ICanScheduler.

Resume

Starts the transmitting task of the cyclic transmitting list and therefore the transfer of all currently registered transmitting objects.

```
HRESULT Resume ( void );
```

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

The function can be used to start all registered transmitting objects simultaneously. Before calling the function all transmitting objects must be set in a started state with the function StartMessage. A subsequent call of this function then guarantees a simultaneous start of all registered transmitting objects.

Suspend

Stops the transmitting task of the cyclic transmitting list and therefore the transfer of all currently registered transmitting objects.

```
HRESULT Suspend ( void );
```

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

The function stops all transmitting objects simultaneously.

Reset

Stops the transmitting task and removes all transmitting objects from the cyclic transmitting list.

```
HRESULT Reset ( void );
```

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

GetStatus

Determines the current state of the transmitting task and of all registered transmitting objects of a cyclic transmitting list.

```
HRESULT GetStatus ( PCANSCHEDULERSTATUS2 pStatus );
```

Parameter

Parameter	Dir.	Description
pStatus	[out]	Pointer to structure of type CANSCHEDULERSTATUS2 . If run successfully the function saves the current settings and the current state of all cyclic transmitting objects in this memory area.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

The function returns in the array [CANSCHEDULERSTATUS2](#).abMsgStat the state of all transmitting objects. The list index returned by function [AddMessage](#) is used to request the state of a transmitting object, this means the array element abMsgStat [Index] contains the state of the transmitting object of the specified index. For further information about the data that are returned by this function see description of the data structure [CANSCHEDULERSTATUS2](#).

AddMessage

Adds a new transmitting object to the cyclic transmitting list.

```
HRESULT AddMessage (
    PCANCYCLICTXMSG2 pMessage,
    PUINT32           pdwIndex );
```

Parameter

Parameter	Dir.	Description
pMessage	[in]	Pointer to initialized structure of type CANCYCLICTXMSG2 with the cyclic transmitting object.
pdwIndex	[out]	Pointer to variable of type UINT32 . If successfully executed, the function returns the list index of the newly added transmitting object of this variable. In case of an error the variable is set to 0xFFFFFFFF. This index is required for all further callings of functions.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

The cyclic transmitting of the newly added transmitting object starts after the successful calling of the function [StartMessage](#). The transmitting list must be simultaneously active (see [Resume](#)).

RemMessage

Stops the processing of a transmitting object and removes it from the cyclic transmitting list.

```
HRESULT RemMessage ( UINT32 dwIndex );
```

Parameter

Parameter	Dir.	Description
dwIndex	[in]	List index of the transmitting object to be removed. The list index must originate from an earlier call of the function AddMessage .

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

After calling the function the list index that is specified in *dwIndex* is invalid and must not be used any more.

StartMessage

Starts the processing of a transmitting object of the cyclic transmitting list.

```
HRESULT StartMessage ( UINT32 dwIndex, UINT16 dwCount );
```

Parameter

Parameter	Dir.	Description
dwIndex	[in]	List index of the transmitting object to be started. The list index must originate from an earlier call of the function AddMessage .
dwCount	[in]	Number of cyclic transmitting repetitions. With value 0 the transmitting is repeated endlessly. The specified value must be in between 0 and 65535.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

The cyclic transmitting exclusively starts if the transmitting task is active when calling the function. If the transmitting task is inactive the transmitting is delayed until the next calling of function [Resume](#).

StopMessage

Stops the processing of a transmitting object of the cyclic transmitting list.

```
HRESULT StopMessage ( UINT32 dwIndex );
```

Parameter

Parameter	Dir.	Description
dwIndex	[in]	List index of the transmitting object to be stopped. The list index must originate from an earlier call of the function AddMessage .

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

7.7 LIN Specific Interface

7.7.1 ILinSocket

The interface contains functions to request for the features and to create message monitors for a LIN controller. The ID of the interface is `IID_ILinSocket`.

GetSocketInfo

Determines general information about the bus controller.

```
HRESULT GetSocketInfo ( PBALSOCKETINFO pSocketInfo );
```

Parameter

Parameter	Dir.	Description
<code>pSocketInfo</code>	[out]	Pointer to structure of type <code>BALSOCKETINFO</code> . If run successfully the function stores the information about the bus controller in this memory area.

Return Value

Return value	Description
<code>VCI_OK</code>	Function succeeded
<code>!=VCI_OK</code>	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

For further information about the data that are returned by this function see description of the data structure `BALSOCKETINFO`.

GetCapabilities

Determines the features of the LIN controller.

```
HRESULT GetCapabilities ( PLINCAPABILITIES pLinCaps );
```

Parameter

Parameter	Dir.	Description
<code>pLinCaps</code>	[out]	Pointer to structure of type <code>LINCAPABILITIES</code> . If run successfully the function stores the features of the LIN controller in this memory area.

Return Value

Return value	Description
<code>VCI_OK</code>	Function succeeded
<code>!=VCI_OK</code>	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

For further information about the data that are returned by this function see description of the data structure `LINCAPABILITIES`.

GetLineStatus

Determines the current settings and the current state of the LIN Controller.

```
HRESULT GetLineStatus ( PLINLINESTATUS pLineStatus );
```

Parameter

Parameter	Dir.	Description
<i>pLineStatus</i>	[out]	Pointer to memory area of type <code>LINLINESTATUS</code> . If run successfully the function saves the current settings and the current state of the controller in this memory area.

Return Value

Return value	Description
<code>VCI_OK</code>	Function succeeded
<code>!=VCI_OK</code>	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

For further information about the data that are returned by this function see description of the data structure [LINLINESTATUS](#).

CreateMonitor

Creates the message monitor for the LIN controller.

```
HRESULT CreateMonitor (
    BOOL          fExclusive,
    PLINMONITOR* ppMonitor );
```

Parameter

Parameter	Dir.	Description
<i>fExclusive</i>	[in]	Determines if the controller is used exclusively for the newly created monitor. If value <code>TRUE</code> is specified no further message monitors can be created after the function ran successfully until the newly generated monitor is released again. If value <code>FALSE</code> is specified as many message monitors as desired can be created for the LIN controller.
<i>ppMonitor</i>	[out]	Address of a variable to which a pointer to the interface <code>ILinMonitor</code> is assigned by the newly created monitor if run successfully. In case of an error the variable is set to <code>NULL</code> .

Return Value

Return value	Description
<code>VCI_OK</code>	Function succeeded
<code>!=VCI_OK</code>	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

For further information see [Message Monitors, p. 50.](#)

7.7.2 ILinControl

The interface provides functions to configure and control a LIN controller. Basic information about functionality of component see [Control Unit, p. 53](#). The ID of the interface is IID_ILinControl.

InitLine

Specifies the operating mode and the bit rate of the LIN controller.

```
HRESULT InitLine ( PLININITLINE pInitParam );
```

Parameter

Parameter	Dir.	Description
<i>pInitParam</i>	[in]	Pointer to initialized structure of type LININITLINE. The field <i>bOpMode</i> determines the operating mode and the field <i>wBitrate</i> the bit rate of the LIN controller. For further information about the fields see description of the data structure LININITLINE .

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

The function internally resets the controller hardware corresponding to the function [ResetLine](#) and initializes the LIN controller with the values specified in *pInitParam*.

ResetLine

Resets the LIN controller to initial state.

```
HRESULT ResetLine ( void );
```

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

For further information see [Control Unit, p. 53](#).

StartLine

Starts the LIN controller.

```
HRESULT StartLine ( void );
```

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

A call of the function is exclusively successful if the LIN controller is configured with the function [InitLine](#). After the function is successful run the LIN controller is connected to the bus (online). Incoming messages are forwarded to all active message monitors resp. transmitting messages are transmitted to the bus. For further information see [Message Monitors, p. 50](#).

StopLine

Stops the LIN controller.

```
HRESULT StopLine ( void );
```

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

Remark

For further information see [Message Monitors, p. 50](#).

WriteMessage

Transmits the specified message either directly to the controller that is connected to the LIN bus or assigns the message to the response table of the controller.

```
HRESULT WriteMessage (BOOL fSend, PLINMSG pLinMsg );
```

Parameter

Parameter	Dir.	Description
fSend	[in]	Determines if a message is directly transmitted to the bus or if it is assigned to the response table of the controller. With TRUE the message is transmitted directly, with FALSE the message is assigned to the response table.
pLinMsg	[in]	Pointer to initialized structure of type LINMSG with the LIN message to be transmitted.

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function VciFormatError

GetLineStatus

Determines the current settings and the current state of the LIN Controller.

```
HRESULT GetLineStatus ( PLINLINESTATUS pLineStatus );
```

Parameter

Parameter	Dir.	Description
<i>pLineStatus</i>	[out]	Pointer to memory area of type <code>LINLINESTATUS</code> . If run successfully the function saves the current settings and the current state of the controller in this memory area.

Return Value

Return value	Description
<code>VCI_OK</code>	Function succeeded
<code>!=VCI_OK</code>	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

For further information about the data that are returned see description of the data structure [`LINLINESTATUS`](#).

7.7.3 ILinMonitor

The interface provides functions to create a message monitor. For further information about the functionality of the component see [Message Monitors, p. 50](#). The ID of the interface is `IID_ILinMonitor`.

Initialize

Initializes the receiving FIFO of the monitor.

```
HRESULT Initialize ( UINT16 wRxSize );
```

Parameter

Parameter	Dir.	Description
<code>wRxSize</code>	[in]	Size of receiving FIFO in number of LIN messages

Return Value

Return value	Description
<code>VCI_OK</code>	Function succeeded
<code>VCI_E_INVALIDARG</code>	Value in parameter <code>wRxSize</code> must be higher than 0.
<code>!=VCI_OK</code>	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

The value specified in parameter `wRxSize` defines the lower limit for the size of the FIFO. The actual size is eventually bigger as specified, because the memory for the FIFOs is reserved page by page and the pages are always used completely. The size of a element in the FIFO always conforms to the size of the structure [`LINMSG`](#).

Activate

Activates the message monitor and connects the receiving FIFO to the LIN controller.

```
HRESULT Activate ( void );
```

Return Value

Return value	Description
<code>VCI_OK</code>	Function succeeded
<code>!=VCI_OK</code>	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

By default the message monitor is deactivated and disconnected from the bus after it is created resp. initialized. To connect the monitor to the bus, the bus must be activated. For further information see [Message Monitors, p. 50](#).

Deactivate

Deactivates the message monitor and connects the receiving FIFO to the LIN controller.

```
HRESULT Deactivate ( void );
```

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

If the monitor is deactivated the monitor does not receive any message from the LIN controller.

GetReader

Determines a pointer to the interface `IFifoReader` of the receiving FIFO of the message monitor.

```
HRESULT GetReader ( IFifoReader** ppReader );
```

Parameter

Parameter	Dir.	Description
<code>ppReader</code>	[out]	Address of a variable to which a pointer to the interface <code>IFifoReader</code> is assigned by the receiving FIFO if run successfully. In case of an error the variable is set to <code>NULL</code> .

Return Value

Return value	Description
VCI_OK	Function succeeded
!=VCI_OK	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

The function succeeds if the monitor is initialized with the function `Initialize`. If the pointer returned by the function is not required any more the pointer must be released with `Release`.

GetStatus

Determines the current state of the message monitor and the LIN controller that is connected to the message monitor.

```
HRESULT GetStatus ( PLINMONITORSTATUS pStatus );
```

Parameter

Parameter	Dir.	Description
<i>pStatus</i>	[out]	Pointer to memory area of type <code>LINMONITORSTATUS</code> . If run successfully the function saves the current settings and the current state of the message monitor in this memory area.

Return Value

Return value	Description
<code>VCI_OK</code>	Function succeeded
<code>!=VCI_OK</code>	Error, further information about error code provides the function <code>VciFormatError</code>

Remark

The function can always be called, even before the first call of one of the function [*Initialize*](#). For further information about the data that are returned see description of the data structure [*LINMONITORSTATUS*](#).

8 Data Structures

8.1 VCI Specific Data Types

The declaration of all VCI specific data types and constants is stored in the files *vcitype.h* and *restype.h*.

8.1.1 VCIID

The data type describes a VCI-wide unique ID resp. a VCI-specific unique ID (LUID).

```
typedef union _VCIID
{
    LUID AsLuid;
    INT64 AsInt64
} VCIID, *PVCIID;
```

Member	Dir.	Description
<i>AsLuid</i>	[out]	ID in form of a LUID. Data type LUID is defined in Windows.
<i>AsInt64</i>	[out]	ID as a signed 64 bit integer

8.1.2 VCIVERSIONINFO

The structure describes the version information.

```
typedef struct _VCIVERSIONINFO
{
    UINT32 VciMajorVersion;
    UINT32 VciMinorVersion;
    UINT32 VciReleaseNumber;
    UINT32 VciBuildNumber;
    UINT32 OsMajorVersion;
    UINT32 OsMinorVersion;
    UINT32 OsBuildNumber;
    UINT32 OsPlatformId;
} VCIVERSIONINFO, *PVCIVERSIONINFO;
```

Member	Dir.	Description
<i>VciMajorVersion</i>	[out]	Major version number of VCI
<i>VciMinorVersion</i>	[out]	Minor version number of VCI
<i>VciRevNumber</i>	[out]	Revision number of VCI
<i>VciBuildNumber</i>	[out]	Build number of VCI
<i>OsMajorVersion</i>	[out]	Major version number of operating system
<i>OsMinorVersion</i>	[out]	Minor version number of operating system
<i>OsBuildNumber</i>	[out]	Build version number of operating system
<i>OsPlatformId</i>	[out]	Platform ID

8.1.3 VCIDEVICEINFO

The structure describes the general information about a device.

```
typedef struct _VCIDEVICEINFO
{
    VCIID VciObjectId;
    GUID DeviceClass;

    UINT8 DriverMajorVersion;
    UINT8 DriverMinorVersion;
    UINT16 DriverBuildVersion

    UINT8 HardwareBranchVersion
    UINT8 HardwareMajorVersion;
    UINT8 HardwareMinorVersion;
    UINT8 HardwareBuildVersion

    union _UniqueHardwareId
    {
        CHAR AsChar[16];
        GUID AsGuid;
    } UniqueHardwareId;

    CHAR Description[128];
    CHAR Manufacturer[126];
    UINT16 DriverReleaseVersion

} VCIDEVICEINFO, *PVCIDEVICEINFO;
```

Member	Dir.	Description
<i>VciObjectId</i>	[out]	Unique VCI ID of device. The VCI assigns a system-wide ID to every started device for the runtime. This ID serves as key for later access to the device.
<i>DeviceClass</i>	[out]	ID of device class. Every device driver specifies its device class in form of a globally unique ID (GUID). Different types of devices belong to different categories.
<i>DriverMajorVersion</i>	[out]	Major version number of device driver
<i>DriverMinorVersion</i>	[out]	Minor version number of device driver
<i>DriverReleaseVersion</i>	[out]	Release number of device driver
<i>DriverBuildVersion</i>	[out]	Build number of device driver
<i>HardwareBranchVersion</i>	[out]	Branch version number of hardware
<i>HardwareMajorVersion</i>	[out]	Major version number of hardware
<i>HardwareMinorVersion</i>	[out]	Minor version number of hardware
<i>HardwareBuildVersion</i>	[out]	Build version number of hardware
<i>UniqueHardwareId</i>	[out]	Unique ID of device. Every device has a unique ID resp. serial number which for example can be used to distinguish between two different cards of the same class. The value can be either interpreted as GUID or as character string. If the first two bytes contain the characters HW it is a serial number in form of a ASCII character string according to ISO-8859-1 (Latin-1).
<i>Description</i>	[out]	Further description of device in form of a 0-terminated ASCII character string according to ISO-8859-1 (Latin-1).
<i>Manufacturer</i>	[out]	Manufacturer ID in form of a 0-terminated ASCII character string according to ISO-8859-1 (Latin-1).

8.1.4 VCIDEVICECAPS

The structure describes the technical features of a device.

```
typedef struct _VCIDEVICECAPS
{
    UINT16 BusCtrlCount;
    UINT16 BusCtrlTypes[VCI_MAX_BUSCTRL];
} VCIDEVICECAPS, *PVCIDEVICECAPS;
```

Member	Dir.	Description
<i>BusCtrlCount</i>	[out]	Number of available bus controllers
<i>BusCtrlTypes</i>	[out]	Table with up to VCI_MAX_BUSCTRL 16 bit values that describe the type of the respective controller. Valid entries in the table are in a range of 0 to <i>BusCtrlCount</i> -1. The upper 8 bits of every value of the table define the type of the supported bus, the lower 8 bits define the type of controller that is used. With the in <i>vctype.h</i> defined macros VCI_BUS_TYPE resp. VCI_CTL_TYPE the type of the bus resp. the type of the controller can be extracted. For predefined constants for all types of bus and controller types see in <i>vctype.h</i> .

8.2 BAL Specific Data Types

The declaration of all BAL specific data types and constants is stored in the files *baltype.h*.

8.2.1 BALFEATURES

The data type describes the features of the Bus Access Layer (BAL) of a controller.

```
typedef struct _BALFEATURES
{
    UINT16 FwMajorVersion;
    UINT16 FwMinorVersion;
    UINT16 BusSocketCount;
    UINT16 BusSocketType[BAL_MAX_SOCKETS];
} BALFEATURES, *PBALFEATURES;
```

Member	Dir.	Description
<i>FwMajorVersion</i>	[out]	Major version number of BAL firmware
<i>FwMinorVersion</i>	[out]	Minor version number of BAL firmware
<i>BusSocketCount</i>	[out]	Number of available bus controllers
<i>BusSocketType</i>	[out]	Table with up to BAL_MAX_SOCKETS 16 bit values that describe the type of the respective controller. Valid entries in the table are in a range of 0 to <i>BusSocketCount</i> -1. The upper 8 bits of every value of the table define the type of the supported bus, the lower 8 bits define the type of controller. With the in <i>vctype.h</i> defined macros VCI_BUS_TYPE resp. VCI_CTL_TYPE the type of the bus resp. the type of the controller can be extracted. Additionally the file contains the predefined constants for each type of possible bus and controller types.



If the value in field *BusSocketCount* does not coincide with the value in field *VCIDEVICECAPS*. *BusCtrlCount* the BAL does not provide all controllers that are available on the device.

8.2.2 BALSOCKETINFO

The data type describes the information about the opened bus controller.

```
typedef struct _BALSOCKETINFO
{
    VCIID Obid;
    UINT16 Type;
    UINT16 BusNo;
} BALSOCKETINFO, *PBALSOCKETINFO;
```

Member	Dir.	Description
<i>Obid</i>	[out]	Unique ID of controller. The ID is only valid until the last reference to the superior BAL object is released.
<i>Type</i>	[out]	Type of connection. The upper 8 bit of the value define the type of the bus the lower 8 bit the type of the controller. With the in <i>vctype.h</i> defined macros <i>VCI_BUS_CTRL</i> resp. <i>VCI_CTL_TYPE</i> the type of the bus resp. the type of the controller can be extracted. The file <i>vctype.h</i> contains several predefined constants for each type of possible bus and controller types.
<i>BusNo</i>	[out]	Number of bus controller. Valid values: 0 to <i>BALFEATURES.BusSocketCount-1</i> .

8.3 CAN Specific Data Types

The declaration of all CAN specific data types and constants is stored in the files *cantype.h*.

8.3.1 CANCAPABILITIES

The data type describes the features of a CAN connection.

```
typedef struct _CANCAPABILITIES
{
    UINT16 wCtrlType;
    UINT16 wBusCoupling;
    UINT16 dwFeatures;
    UINT32 dwClockFreq;
    UINT32 dwTscDivisor;
    UINT32 dwCmsDivisor;
    UINT32 dwMaxCmsTicks;
    UINT32 dwDtxDivisor;
    UINT32 dwMaxDtxTicks;
} CANCAPABILITIES1, *PCANCAPABILITIES;
```

Member	Dir.	Description	
<i>wCtrlType</i>	[out]	Type of CAN controller. The value of this field is corresponding to a <i>CAN_TYPE_</i> constant defined in <i>cantype.h</i> .	
<i>wBusCoupling</i>	[out]	Type of bus coupling. For the bus coupling the following values are defined:	
		CAN_BUSC_LOWSPEED	CAN-Controller has a low speed coupling.
		CAN_BUSC_HIGHSPEED	CAN-Controller has a high speed coupling.
<i>dwFeatures</i>	[out]	Supported features. Value is a logical combination of one or more of the following constants:	
		CAN_FEATURE_STDOREXT	CAN controller supports 11 or 29 bit messages, but not both formats simultaneously.
		CAN_FEATURE_STDANDEXT	CAN controller supports 11 or 29 bit messages simultaneously.
		CAN_FEATURE_RMTFRAME	CAN controller supports remote transmission request (RTR) messages.
		CAN_FEATURE_ERRFRAME	CAN controller returns error messages.
		CAN_FEATURE_BUSLOAD	CAN controller supports calculation of the bus load.

Member	Dir.	Description
		<p>CAN_FEATURE_IDFILTER CAN controller allows exact filtering of messages.</p> <p>CAN_FEATURE_LISTONLY CAN controller supports operating mode <i>Listen Only</i>.</p> <p>CAN_FEATURE_SCHEDULER Cyclic transmission list provided.</p> <p>CAN_FEATURE_GENERRFRM CAN controller supports generating of error frames.</p> <p>CAN_FEATURE_DELAYEDTX CAN controller supports delayed transmitting of messages.</p> <p>CAN_FEATURE_SINGLESHOT CAN controller supports messages of type <i>Single Shot</i>. If a message is of type <i>Single Shot</i> the controller does not try to transmit again if the message is not transmitted with the first attempt.</p> <p>CAN_FEATURE_HIGHPRIOR CAN controller supports transmitting of messages with high priority. Messages with high priority are assigned to a transmitting buffer by the controller, the transmitting buffer is prior to messages in the normal transmitting buffer. Messages of high priority are transmitted with priority to the bus.</p> <p>CAN_FEATURE_AUTOBAUD CAN controller supports the automatic detection of the bit rate regarding the hardware. If this bit is set and the controller is connected to a running system, the controller detects the bit rate autonomously and it can be initialized without specifying bit timing parameters (see CANINITLINE).</p>
<i>dwClockFreq</i>	[out]	Frequency in hertz of the primary clock generator
<i>dwTscDivisor</i>	[out]	Divisor for the time stamp counter. Resolution of the time stamps of CAN messages is calculated by the values specified here divided by the frequency of the primary clock generator.
<i>dwCmsDivisor</i>	[out]	Divisor for the clock generator of the cyclic transmitting list. Frequency of cyclic transmitting list is calculated by the frequency of the primary clock generator divided by the value specified here. If no cyclic transmitting list is available the field contains value 0.
<i>dwCmsMaxTicks</i>	[out]	Maximum cyclic time of the cyclic transmitting list in timer ticks. If no cyclic transmitting list is available the field contains value 0.
<i>dwDtxDivisor</i>	[out]	Divisor for the clock generator for delayed transmitting of CAN messages. The resolution of the timer for delayed transmission is calculated by the values specified here divided by the frequency of the primary clock generator. If delayed transmitting is not supported the field contains value 0.
<i>dwDtxMaxTicks</i>	[out]	Maximum delay time in number of timer ticks. If delayed transmitting is not supported the field contains value 0.

8.3.2 CANCAPABILITIES2

The data type describes the features of a extended CAN connection.

```
typedef struct _CANCAPABILITIES2
{
    UINT16 wCtrlType;
    UINT16 wBusCoupling;
    UINT32 dwFeatures;

    UINT32 dwCanClkFreq;
    CANBTP sSdrRangeMin;
    CANBTP sSdrRangeMax;
    CANBTP sFdrRangeMin;
    CANBTP sFdrRangeMax;

    UINT32 dwTscClkFreq;
    UINT32 dwTscDivisor;

    UINT32 dwCmsClkFreq;
    UINT32 dwCmsDivisor;
    UINT32 dwCmsMaxTicks;

    UINT32 dwDtxClkFreq;
    UINT32 dwDtxDivisor;
    UINT32 dwDtxMaxTicks;
} CANCAPABILITIES2, *PCANCAPABILITIES2;
```

Member	Dir.	Description
<i>CtrlType</i>	[out]	Type of CAN controller. The value of this field is corresponding to a CAN_TYPE_ constant defined in <i>cantype.h</i> .
<i>wBusCoupling</i>	[out]	Type of bus coupling. For the bus coupling the following values are defined: CAN_BUSC_LOWSPEED CAN Controller has a low speed coupling. CAN_BUSC_HIGHSPEED CAN Controller has a high speed coupling.
<i>dwFeatures</i>	[out]	Supported features. Value is a logical combination of one or more of the following constants: CAN_FEATURE_STDREEXT CAN controller supports 11 or 29 bit messages, but not both formats simultaneously. CAN_FEATURE_STDANDEXT CAN controller supports 11 or 29 bit messages simultaneously. CAN_FEATURE_RMTFRAME CAN controller supports remote transmission request (RTR) messages. CAN_FEATURE_ERRFRAME CAN controller returns error messages. CAN_FEATURE_BUSLOAD CAN controller supports calculation of the bus load. CAN_FEATURE_IDFILTER CAN controller allows exact filtering of messages. CAN_FEATURE_LISTONLY CAN controller supports operating mode <i>Listen Only</i> . CAN_FEATURE_SCHEDULER Cyclic transmitting list provided. CAN_FEATURE_GENERRFRM CAN controller supports generating of error frames. CAN_FEATURE_DELAYEDTX CAN controller supports delayed transmitting of messages. CAN_FEATURE_SINGLESHOT CAN controller supports messages of type <i>Single Shot</i> . If a message is of type <i>Single Shot</i> the controller does not try to transmit again if the message is not transmitted with the first attempt. CAN_FEATURE_HIGHPRIOR CAN controller supports transmitting of messages with high priority. Messages with high priority are assigned to a transmitting buffer by the controller,

Member	Dir.	Description
		<p>CAN_FEATURE_AUTOBAUD : the transmitting buffer is prior to messages in the normal transmitting buffer. Messages of high priority are transmitted with priority to the bus.</p> <p>CAN_FEATURE_EXTDATA : CAN controller supports the automatic detection of the bit rate. If this bit is set, the controller detects if it is connected to a running system, the bit rate autonomously and it can be initialized without specifying bit timing parameters (see CANINITLINE2).</p> <p>CAN_FEATURE_FASTDATA : CAN controller provides messages with extended data field. If this bit is not set at a CAN FD controller it supports maximally 8 byte in the data field.</p> <p>CAN_FEATURE_ISOFRAME : CAN controller supports transmission with high data bit rate.</p> <p>CAN_FEATURE_NONISOFRM : CAN controller supports ISO-conform frames (exclusively CAN FD).</p>
<i>dwCanClockFreq</i>	[out]	Frequency in Hertz of bit rate generator. The bit rate generator defines together with the values in the structure CANBTP the bit transmission rate for the standard resp. for the nominal arbitration bit rate and the high data bit rate.
<i>sSdrRangeMin</i>	[out]	Lower limit value to specify the bit rate generator for the standard resp. the nominal arbitration bit rate.
<i>sSdrRangeMax</i>	[out]	Upper limit value to specify the bit rate generator for the standard resp. the nominal arbitration bit rate.
<i>sFdrRangeMin</i>	[out]	Lower limit value to specify the bit rate generator for the high data bit rate. All fields of the structure contain the value 0 if the controller do not support a high data bit rate. See CAN_FEATURE_FASTDATA.
<i>sFdrRangeMax</i>	[out]	Upper limit value to specify the bit rate generator for the high data bit rate. All fields of the structure contain the value 0 if the controller do not support a high data bit rate. See CAN_FEATURE_FASTDATA.
<i>dwTscClockFreq</i>	[out]	Frequency in Hertz of clock generator which is used to create the time stamps of CAN messages (Time Stamp Counter).
<i>dwTscDivisor</i>	[out]	Divisor for clock generator for creating time stamps. Resolution of the time stamps of CAN messages is calculated by the values specified here divided by the frequency of the time stamp counter.
<i>dwCmsClockFreq</i>	[out]	Frequency in Hertz of the clock generator of the cyclic transmitting list (Cyclic Message Timer). If no cyclic transmitting list is available the field contains value 0.
<i>dwCmsDivisor</i>	[out]	Divisor for the clock generator of the cyclic transmitting list. Frequency of cyclic transmitting list is calculated by the frequency of the cyclic message timer divided by the value specified here. If no cyclic transmitting list is available the field contains value 0.
<i>dwCmsMaxTicks</i>	[out]	Maximum cyclic time of the cyclic transmitting list in timer ticks. If no cyclic transmitting list is available the field contains value 0.
<i>dwDtxClockFreq</i>	[out]	Frequency in Hertz of clock generator, that is used for delayed transmission of CAN messages (Delay Timer). If delayed transmission is not supported the field contains value 0.
<i>dwDtxDivisor</i>	[out]	Divisor for the clock generator for delayed transmission of messages. The resolution of the timer for delayed transmission of messages is calculated by the values specified here divided by the frequency of the delay timer. If delayed transmission is not supported the field contains value 0.
<i>dwDtxMaxTicks</i>	[out]	Maximum delay time in number of timer ticks. If delayed transmission is not supported the field contains value 0.

8.3.3 CANBRTABLE

The data structure serves to determine the bit rate and is used by the function `ICanControl::DetectBaud`.

```
typedef struct _CANBRTABLE
{
    UINT8 bCount;
    UINT8 bIndex;
    UINT8 abBtr0[64];
    UINT8 abBtr1[64];
} CANBRTABLE, *PCANBRTABLE;
```

Member	Dir.	Description
<i>bCount</i>	[in]	Number of valid entries in the tables <i>abBtr0</i> and <i>abBtr1</i> . The first valid value has to be set in <i>abBtr0[0]</i> resp. <i>abBtr1[0]</i> .
<i>bIndex</i>	[in/out]	If run successfully <i>DetectBaud</i> returns in this field the table index of the detected bus timing values. Before calling additional characters for the CAN operating mode used in <i>DetectBaud</i> can be specified here. Valid are exclusively <code>CAN_OPMODE_LOWSPEED</code> or 0, if no low speed coupling is desired.
<i>abBtr0</i>	[in]	Table with up to 64 values for the bus timing register 0. This values are used to determine the actual transmission rate on the bus. The value of an entry corresponds to the <i>BT0</i> register of Philips SJA 1000 CAN controller with a clock frequency of 16 MHz.
<i>abBtr1</i>	[in]	Table with up to 64 values for the bus timing register 1. This values are used to determine the actual transmission rate on the bus. The value of an entry corresponds to the <i>BT1</i> register of Philips SJA 1000 CAN controller with a clock frequency of 16 MHz.

8.3.4 CANBTP

The data structure defines the parameters to specify the bit transmission rate and the sampling point.

```
typedef struct _CANBTP
{
    UINT32 dwMode;
    UINT32 dwBPS;
    UINT16 wTS1;
    UINT16 wTS2;
    UINT16 wSJW;
    UINT16 wTDO;
} CANBTP, *PCANBTP;
```

Member	Dir.	Description
<i>dwMode</i>	[in]	Operating mode. This bit field determines how the following fields are interpreted. For the operating mode a logical combination of one or more of the following constants can be specified: CAN_BTMODE_RAW: Native mode. The fields <i>dwBPS</i> , <i>wTS1</i> , <i>wTS2</i> , <i>wSJW</i> and <i>wTDO</i> contain hardware specific values for the corresponding registers of the controller. The values of these fields must be inside the limits which are determined by the fields <i>sSdrRangeMin</i> resp. <i>sFdrRangeMin</i> and <i>sSdrRangeMax</i> resp. <i>sFdrRangeMax</i> of structure CANCAPABILITIES2 . CAN_BTMODE_TSM: Activating triple sampling mode
<i>dwBPS</i>	[in]	Transmitting rate in bits per second. If in field <i>dwMode</i> the bit CAN_BTMODE_RAW is set, the hardware specific value for the baud rate prescaler register is expected here. If not, the bit rate in bits per second is expected.
<i>wTS1</i>	[in]	Length of time segment 1. If in field <i>dwMode</i> the bit CAN_BTMODE_RAW is set, the hardware specific number of time quanta for the time segment 1 is expected here. If not, the value defines the length of this time segment in relation to the total number of time quanta per bit.
<i>wTS2</i>	[in]	Length of time segment 2. If in field <i>dwMode</i> the bit CAN_BTMODE_RAW is set, the hardware specific number of time quanta for the time segment 2 is expected here. If not, the value defines the length of this time segment in relation to the total number of time quanta per bit.
<i>wSJW</i>	[in]	Jump width for re-synchronization. If in field <i>dwMode</i> the bit CAN_BTMODE_RAW is set, the hardware specific number of time quanta for the re-synchronization is expected here. If not, the value defines the length of the jumping width in relation to the total number of time quanta per bit.
<i>wTDO</i>	[in]	Offset to the transceiver delay automatically determined by the controller. If in field <i>dwMode</i> the bit CAN_BTMODE_RAW is set, the hardware specific number of time quanta for the transceiver delay is expected here. If not, the value defines the length of the transceiver delay offset in relation to the total number of time quanta per bit. This value is exclusively relevant with fast data bit rate.

8.3.5 CANBTPTABLE

The data structure serves to detect the nominal bit rate and the fast bit rate if supported by the computer. The structure is used by function `ICanControl2::DetectBaud`.

```
typedef struct _CANBTPTABLE
{
    UINT8 bCount;
    UINT8 bIndex;
    struct
    {
        CANBTP sSdr;
        CANBTP sFdr;
    } asBTP[64];
} CANBTPTABLE, *PCANBTPTABLE;
```

Member	Dir.	Description
<i>bCount</i>	[in]	Number of valid values in table <i>asBTP</i> . The first valid values have to be set in <i>asBTP[0]</i> .
<i>bIndex</i>	[out]	Table index with the bit timing parameters of the detected bit rate
<i>asBTP</i>	[in]	Table with up to 64 values of different default values, that can be used to determine the actual bit transmission rate on the bus. The table contains the paired bit timing parameters for the default and the nominal bit rate in field <i>sSdr</i> and the fast bit rate in field <i>sFdr</i> . The values for the fast data bit rate are only relevant if the controller supports this and if in parameter <i>bExMode</i> the value <code>CAN_EXMODE_FASTDATA</code> is specified when calling the function <code>ICanControl2::DetectBaud</code> . Otherwise the values in <i>sFdr</i> have no significance.

8.3.6 CANINITLINE

The structure is used to initialize the CAN control unit.

```
typedef struct _CANINITLINE
{
    UINT8 bOpMode;
    UINT8 bReserved;
    UINT8 bBtReg0;  UINT8 bBtReg1;
} CANINITLINE, *PCANINITLINE;
```

Member	Dir.	Description												
<i>bOpMode</i>	[in]	<p>Operating mode of controller. For the operating mode a logical combination of one or more of the following constants can be specified:</p> <table> <tr> <td>CAN_OPMODE_STANDARD</td><td>Controller accepts messages with 11 bit identifier.</td></tr> <tr> <td>CAN_OPMODE_EXTENDED</td><td>Controller accepts messages with 29 bit identifier.</td></tr> <tr> <td>CAN_OPMODE_LISTONLY</td><td>Controller is used in <i>Listen Only</i> mode.</td></tr> <tr> <td>CAN_OPMODE_ERRFRAME</td><td>Errors are reported to the application via special messages.</td></tr> <tr> <td>CAN_OPMODE_LOWSPEED</td><td>Controller uses low speed bus coupling.</td></tr> <tr> <td>CAN_OPMODE_AUTOBAUD</td><td>If supported by the controller the controller performs an automatic detection of the bit rate during the initialization. Controller must be connected with running system. If this bit is set the bit timing parameters specified in the fields <i>bBtReg0</i> and <i>bBtReg1</i> are ignored.</td></tr> </table>	CAN_OPMODE_STANDARD	Controller accepts messages with 11 bit identifier.	CAN_OPMODE_EXTENDED	Controller accepts messages with 29 bit identifier.	CAN_OPMODE_LISTONLY	Controller is used in <i>Listen Only</i> mode.	CAN_OPMODE_ERRFRAME	Errors are reported to the application via special messages.	CAN_OPMODE_LOWSPEED	Controller uses low speed bus coupling.	CAN_OPMODE_AUTOBAUD	If supported by the controller the controller performs an automatic detection of the bit rate during the initialization. Controller must be connected with running system. If this bit is set the bit timing parameters specified in the fields <i>bBtReg0</i> and <i>bBtReg1</i> are ignored.
CAN_OPMODE_STANDARD	Controller accepts messages with 11 bit identifier.													
CAN_OPMODE_EXTENDED	Controller accepts messages with 29 bit identifier.													
CAN_OPMODE_LISTONLY	Controller is used in <i>Listen Only</i> mode.													
CAN_OPMODE_ERRFRAME	Errors are reported to the application via special messages.													
CAN_OPMODE_LOWSPEED	Controller uses low speed bus coupling.													
CAN_OPMODE_AUTOBAUD	If supported by the controller the controller performs an automatic detection of the bit rate during the initialization. Controller must be connected with running system. If this bit is set the bit timing parameters specified in the fields <i>bBtReg0</i> and <i>bBtReg1</i> are ignored.													
<i>bReserved</i>	[in]	Reserved. Value must be initialized with 0.												
<i>bBtReg0</i>	[in]	Value for the bus timing register 0 of the controller. Value corresponds to BTRO register of Philips SJA 1000 CAN controllers with a clock frequency of 16 MHz. Further information see data sheet of SJA 1000.												
<i>bBtReg1</i>	[in]	Value for the bus timing register 1 of the controller. Value corresponds to BTR1 register of Philips SJA 1000 CAN controllers with a clock frequency of 16 MHz. Further information see data sheet of SJA 1000.												

8.3.7 CANINITLINE2

The structure is used to initialize the extended CAN control unit.

```
typedef struct _CANINITLINE2
{
    UINT8 bOpMode;
    UINT8 bExMode;
    UINT8 bSFMode;
    UINT8 bEFMode;
    UINT32 dwSFIds;
    UINT32 dwEFIds;
    CANBTP sBtpSdr;
    CANBTP sBtpFdr;
} CANINITLINE2, *PCANINITLINE2;
```

Member	Dir.	Description												
<i>bOpMode</i>	[in]	<p>Operating mode of controller. For the operating mode a logical combination of one or more of the following constants can be specified:</p> <table> <tr> <td>CAN_OPMODE_STANDARD</td><td>Controller accepts messages with 11 bit identifier.</td></tr> <tr> <td>CAN_OPMODE_EXTENDED</td><td>Controller accepts messages with 29 bit identifier.</td></tr> <tr> <td>CAN_OPMODE_LISTONLY</td><td>Controller is used in <i>Listen Only</i> mode.</td></tr> <tr> <td>CAN_OPMODE_ERRFRAME</td><td>Errors are reported to the application via special messages.</td></tr> <tr> <td>CAN_OPMODE_LOWSPEED</td><td>Controller uses low speed bus coupling.</td></tr> <tr> <td>CAN_OPMODE_AUTOBAUD</td><td>If supported by the controller the controller performs an automatic detection of the bit rate during the initialization. Controller must be connected with running system. If this bit is set the bit timing parameters specified in the fields <i>sBtpSdr</i> and <i>sBtpFdr</i> are ignored.</td></tr> </table>	CAN_OPMODE_STANDARD	Controller accepts messages with 11 bit identifier.	CAN_OPMODE_EXTENDED	Controller accepts messages with 29 bit identifier.	CAN_OPMODE_LISTONLY	Controller is used in <i>Listen Only</i> mode.	CAN_OPMODE_ERRFRAME	Errors are reported to the application via special messages.	CAN_OPMODE_LOWSPEED	Controller uses low speed bus coupling.	CAN_OPMODE_AUTOBAUD	If supported by the controller the controller performs an automatic detection of the bit rate during the initialization. Controller must be connected with running system. If this bit is set the bit timing parameters specified in the fields <i>sBtpSdr</i> and <i>sBtpFdr</i> are ignored.
CAN_OPMODE_STANDARD	Controller accepts messages with 11 bit identifier.													
CAN_OPMODE_EXTENDED	Controller accepts messages with 29 bit identifier.													
CAN_OPMODE_LISTONLY	Controller is used in <i>Listen Only</i> mode.													
CAN_OPMODE_ERRFRAME	Errors are reported to the application via special messages.													
CAN_OPMODE_LOWSPEED	Controller uses low speed bus coupling.													
CAN_OPMODE_AUTOBAUD	If supported by the controller the controller performs an automatic detection of the bit rate during the initialization. Controller must be connected with running system. If this bit is set the bit timing parameters specified in the fields <i>sBtpSdr</i> and <i>sBtpFdr</i> are ignored.													
<i>bExMode</i>	[in]	<p>Extended operating mode. If supported by the controller, a logical combination of one or more of the following constants can be specified:</p> <table> <tr> <td>CAN_EXMODE_EXTDATA</td><td>Allows messages with extended data length up to 64 bytes.</td></tr> <tr> <td>CAN_EXMODE_FASTDATA</td><td>Allows higher bit rates for the data field.</td></tr> <tr> <td>CAN_EXMODE_NONISO:</td><td>Use of non-ISO-conform message frames. This option is exclusively available with older CAN FD controller with the feature CAN_FEATURE_NONISOFRM.</td></tr> </table> <p>If the value CAN_EXMODE_DISABLED is specified no further operating mode is activated. The value also must be specified with all other controllers that do not support CAN FD operating mode. Further information see description of field <i>dwFeatures</i> of structure CANCAPABILITIES2.</p>	CAN_EXMODE_EXTDATA	Allows messages with extended data length up to 64 bytes.	CAN_EXMODE_FASTDATA	Allows higher bit rates for the data field.	CAN_EXMODE_NONISO:	Use of non-ISO-conform message frames. This option is exclusively available with older CAN FD controller with the feature CAN_FEATURE_NONISOFRM.						
CAN_EXMODE_EXTDATA	Allows messages with extended data length up to 64 bytes.													
CAN_EXMODE_FASTDATA	Allows higher bit rates for the data field.													
CAN_EXMODE_NONISO:	Use of non-ISO-conform message frames. This option is exclusively available with older CAN FD controller with the feature CAN_FEATURE_NONISOFRM.													
<i>bSFMode</i>	[in]	Default value for the operating mode of 11 bit filter. Operating mode can also be changed with function ICanControl2::SetFilterMode .												
<i>bEFMode</i>	[in]	Default value for the operating mode of 29 bit filter. Operating mode can also be changed with function ICanControl2::SetFilterMode .												
<i>dwSFIds</i>	[in]	Number of CAN IDs supported by the 11 bit filter. With value 0 not filter is specified. Controller allows all messages with 11 bit ID to pass. The operating mode specified in <i>bSFMode</i> is not considered.												
<i>dwEFIds</i>	[in]	Number of CAN IDs supported by the 29 bit filter. With value 0 not filter is specified. Controller allows all messages with 29 bit ID to pass. The operating mode specified in <i>bEFMode</i> is not considered.												
<i>sBtpSdr</i>	[in]	Bit timing parameter for default or nominal bit rate resp. for bit rate during the arbitration phase. For further information see description of data type CANBTP .												
<i>sBtpFdr</i>	[in]	Bit timing parameter for fast data bit rate. Field is exclusively relevant if the controller supports the fast data transmission and if constant CAN_EXMODE_FASTDATA in field <i>bExMode</i> is specified. For further information see description of data type CANBTP .												

8.3.8 CANLINESTATUS

The data type describes the current status of a CAN control unit.

```
typedef struct _CANLINESTATUS
{
    UINT8 bOpMode;
    UINT8 bBtReg0;
    UINT8 bBtReg1;
    UINT8 bBusLoad;
    UINT32 dwStatus;
} CANLINESTATUS, *PCANLINESTATUS;
```

Member	Dir.	Description												
<i>bOpMode</i>	[in]	Current operating mode of controller. Value is a logical combination of one or more in <i>cantype.h</i> defined constants <code>CAN_OPMODE</code> and corresponds to the value of the field <i>bOpMode</i> specified in parameter <i>pInitLine</i> when calling the function <code>ICanControl::InitLine</code> .												
<i>bBtReg0</i>	[out]	Current value Bus-Timing-Register 0. Value corresponds to <i>BTR0</i> register of Philips SJA 1000 CAN controllers with a clock frequency of 16 MHz. Further information see data sheet of SJA 1000.												
<i>bBtReg1</i>	[out]	Current value bus timing register 1. Value corresponds to <i>BTR1</i> register of Philips SJA 1000 CAN controllers with a clock frequency of 16 MHz. Further information see data sheet of SJA 1000.												
<i>bBusLoad</i>	[out]	Bus load in the second before the call of the function in percentage (0 to 100). Value shows a state. To monitor the bus load over a time span use appropriate analysis tools. Value is exclusively valid if calculation of bus load is supported by the controller (see CANCAPABILITIES).												
<i>dwStatus</i>	[out]	<p>Current status of CAN controller. Value is a logical combination of one or more of the following constants:</p> <table> <tbody> <tr> <td>CAN_STATUS_TXPEND</td> <td>CAN controller is currently transmitting a message to the bus.</td> </tr> <tr> <td>CAN_STATUS_OVRRUN</td> <td>Data overflow in the receiving buffer of the CAN controller had happened.</td> </tr> <tr> <td>CAN_STATUS_ERRLIM</td> <td>Overflow of an error counter of the CAN controller has happened.</td> </tr> <tr> <td>CAN_STATUS_BUSOFF</td> <td>CAN controller has shifted to state <i>BUS-OFF</i>.</td> </tr> <tr> <td>CAN_STATUS_ININIT</td> <td>CAN controller is in stopped state.</td> </tr> <tr> <td>CAN_STATUS_BUSCERR</td> <td>Faulty bus coupling, only relevant with CAN interfaces with CAN low-speed transceiver and activated low-speed CAN bus. The output pin <i>ERR</i> of the CAN low-speed transceiver is low active. If the output pin <i>ERR</i> of the CAN low-speed transceiver is set to 0, the flag <code>DCAN_STATUS_BUSCERR</code> in the CAN controller status is set to 1. If the output pin <i>ERR</i> of the CAN low-speed transceiver is set to 1, the flag <code>DCAN_STATUS_BUSCERR</code> in the CAN controller status is set to 0. This means, if an error occurs on the CAN bus line of the CAN low-speed transceiver, the flag <code>DCAN_STATUS_BUSCERR</code> in the CAN controller status is set to 1.</td> </tr> </tbody> </table>	CAN_STATUS_TXPEND	CAN controller is currently transmitting a message to the bus.	CAN_STATUS_OVRRUN	Data overflow in the receiving buffer of the CAN controller had happened.	CAN_STATUS_ERRLIM	Overflow of an error counter of the CAN controller has happened.	CAN_STATUS_BUSOFF	CAN controller has shifted to state <i>BUS-OFF</i> .	CAN_STATUS_ININIT	CAN controller is in stopped state.	CAN_STATUS_BUSCERR	Faulty bus coupling, only relevant with CAN interfaces with CAN low-speed transceiver and activated low-speed CAN bus. The output pin <i>ERR</i> of the CAN low-speed transceiver is low active. If the output pin <i>ERR</i> of the CAN low-speed transceiver is set to 0, the flag <code>DCAN_STATUS_BUSCERR</code> in the CAN controller status is set to 1. If the output pin <i>ERR</i> of the CAN low-speed transceiver is set to 1, the flag <code>DCAN_STATUS_BUSCERR</code> in the CAN controller status is set to 0. This means, if an error occurs on the CAN bus line of the CAN low-speed transceiver, the flag <code>DCAN_STATUS_BUSCERR</code> in the CAN controller status is set to 1.
CAN_STATUS_TXPEND	CAN controller is currently transmitting a message to the bus.													
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CAN_STATUS_ERRLIM	Overflow of an error counter of the CAN controller has happened.													
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CAN_STATUS_BUSCERR	Faulty bus coupling, only relevant with CAN interfaces with CAN low-speed transceiver and activated low-speed CAN bus. The output pin <i>ERR</i> of the CAN low-speed transceiver is low active. If the output pin <i>ERR</i> of the CAN low-speed transceiver is set to 0, the flag <code>DCAN_STATUS_BUSCERR</code> in the CAN controller status is set to 1. If the output pin <i>ERR</i> of the CAN low-speed transceiver is set to 1, the flag <code>DCAN_STATUS_BUSCERR</code> in the CAN controller status is set to 0. This means, if an error occurs on the CAN bus line of the CAN low-speed transceiver, the flag <code>DCAN_STATUS_BUSCERR</code> in the CAN controller status is set to 1.													

8.3.9 CANLINESTATUS2

The data type describes the current status of a CAN control unit.

```
typedef struct _CANLINESTATUS
{
    UINT8 bOpMode;
    UINT8 bExMode;
    UINT8 bBusLoad;
    UINT8 bReserved;
    CANBTP sBtpSdr;
    CANBTP sBtpFdr;
    UINT32 dwStatus;
} CANLINESTATUS2, *PCANLINESTATUS2;
```

Member	Dir.	Description												
<i>bOpMode</i>	[in]	Current operating mode of controller. Value is a logical combination of one or more in <i>cantype.h</i> defined constants <code>CAN_OPMODE</code> and corresponds to the value of the field <i>bOpMode</i> specified in parameter <i>pInitLinew</i> when calling the function <code>ICanControl2::InitLine</code> .												
<i>bExMode</i>	[in]	Current extended operating mode of controller. Value is a logical combination of one or more in <i>cantype.h</i> defined constants <code>CAN_EXMODE</code> and corresponds to the value of the field <i>bExMode</i> specified in parameter <i>pInitLinew</i> when calling the function <code>ICanControl2::InitLine</code> .												
<i>bBusLoad</i>	[out]	Bus load in the second before the call of the function in percentage (0 to 100). Value shows a state. To monitor the bus load over a time span use appropriate analysis tools. Value is exclusively valid if calculation of bus load is supported by the controller (see CANCAPABILITIES2).												
<i>bReserved</i>		Not used (normally 0)												
<i>sBtpSdr</i>	[out]	Current bit timing parameter for nominal bit rate resp. for bit rate during the arbitration phase												
<i>sBtpFdr</i>	[out]	Current bit timing parameter for fast data bit rate												
<i>dwStatus</i>	[out]	Current status of CAN controller. Value is a logical combination of one or more of the following constants: <table> <tr> <td>CAN_STATUS_TXPEND</td> <td>CAN controller is currently transmitting a message to the bus.</td> </tr> <tr> <td>CAN_STATUS_OVRRUN</td> <td>Data overflow in the receiving buffer of the CAN controller had happened.</td> </tr> <tr> <td>CAN_STATUS_ERRLIM</td> <td>Overflow of an error counter of the CAN controller has happened.</td> </tr> <tr> <td>CAN_STATUS_BUSOFF</td> <td>CAN controller has shifted to state <i>BUS-OFF</i>.</td> </tr> <tr> <td>CAN_STATUS_ININIT</td> <td>CAN controller is in stopped state.</td> </tr> <tr> <td>CAN_STATUS_BUSCERR</td> <td>Faulty bus coupling, only relevant with CAN interfaces with CAN low-speed transceiver and activated low-speed CAN bus. The output pin <i>ERR</i> of the CAN low-speed transceiver is low active. If the output pin <i>ERR</i> of the CAN low-speed transceiver is set to 0, the flag <code>DCAN_STATUS_BUSCERR</code> in the CAN controller status is set to 1. If the output pin <i>ERR</i> of the CAN low-speed transceiver is set to 1, the flag <code>DCAN_STATUS_BUSCERR</code> in the CAN controller status is set to 0. This means, if an error occurs on the CAN bus line of the CAN low-speed transceiver, the flag <code>DCAN_STATUS_BUSCERR</code> in the CAN controller status is set to 1.</td> </tr> </table>	CAN_STATUS_TXPEND	CAN controller is currently transmitting a message to the bus.	CAN_STATUS_OVRRUN	Data overflow in the receiving buffer of the CAN controller had happened.	CAN_STATUS_ERRLIM	Overflow of an error counter of the CAN controller has happened.	CAN_STATUS_BUSOFF	CAN controller has shifted to state <i>BUS-OFF</i> .	CAN_STATUS_ININIT	CAN controller is in stopped state.	CAN_STATUS_BUSCERR	Faulty bus coupling, only relevant with CAN interfaces with CAN low-speed transceiver and activated low-speed CAN bus. The output pin <i>ERR</i> of the CAN low-speed transceiver is low active. If the output pin <i>ERR</i> of the CAN low-speed transceiver is set to 0, the flag <code>DCAN_STATUS_BUSCERR</code> in the CAN controller status is set to 1. If the output pin <i>ERR</i> of the CAN low-speed transceiver is set to 1, the flag <code>DCAN_STATUS_BUSCERR</code> in the CAN controller status is set to 0. This means, if an error occurs on the CAN bus line of the CAN low-speed transceiver, the flag <code>DCAN_STATUS_BUSCERR</code> in the CAN controller status is set to 1.
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8.3.10 CANCHANSTATUS

The data type describes the current status of the CAN message channel.

```
typedef struct _CANLINESTATUS
{
    CANLINESTATUS sLineStatus;
    BOOL32 fActivated;
    BOOL32 fRxOverrun;
    UINT8 bRxFifoLoad;
    UINT8 bTxFifoLoad;
} CANCHANSTATUS, *PCANCHANSTATUS;
```

Member	Dir.	Description
<i>sLineStatus</i>	[out]	Current status of CAN controller. For further information see CANLINESTATUS .
<i>fActivated</i>	[out]	Shows if message channel is active (TRUE) or inactive (FALSE).
<i>fRxOverrun</i>	[out]	Signalizes an overflow in the receiving buffer with the value TRUE.
<i>bRxFifoLoad</i>	[out]	Current filling level of receiving FIFO in percentage
<i>bTxFifoLoad</i>	[out]	Current filling level of transmitting FIFO in percentage

8.3.11 CANCHANSTATUS2

The data type describes the current status of the CAN message channel with extended interface.

```
typedef struct _CANCHANSTATUS2
{
    CANLINESTATUS sLineStatus;
    BOOL8 fActivated;
    BOOL8 fRxOverrun;
    UINT8 bRxFifoLoad;
    UINT8 bTxFifoLoad;
} CANCHANSTATUS, *PCANCHANSTATUS2;
```

Member	Dir.	Description
<i>sLineStatus</i>	[out]	Current status of CAN controller. For further information see CANLINESTATUS2 .
<i>fActivated</i>	[out]	Shows if message channel is active (TRUE) or inactive (FALSE).
<i>fRxOverrun</i>	[out]	Signalizes an overflow in the receiving buffer with the value TRUE.
<i>bRxFifoLoad</i>	[out]	Current filling level of receiving FIFO in percentage
<i>bTxFifoLoad</i>	[out]	Current filling level of transmitting FIFO in percentage

8.3.12 CANSCHEDULERSTATUS

The data type describes the current status of the cyclic transmitting list.

```
typedef struct _CANSCHEDULERSTATUS
{
    UINT8 bTaskStat;
    UINT8 abMsgStat[16];
} CANSCHEDULERSTATUS, *PCANSCHEDULERSTATUS;
```

Member	Dir.	Description
<i>bTaskStat</i>	[out]	Current status of transmitting task CAN_CXTTSK_STAT_STOPPED Transmitting task is stopped resp. deactivated. CAN_CXTTSK_STAT_RUNNING Transmitting task is performed resp. is active.
<i>abMsgStat</i>		Table with status of all 16 transmitting objects. Each table entry can take one of the following values: CAN_CTXMSG_STAT_EMPTY The entry is not assigned to a transmitting object resp. the entry is currently not used. CAN_CTXMSG_STAT_BUSY Transmitting object is currently processed. CAN_CTXMSG_STAT_DONE Processing of transmitting object is finished.

8.3.13 CANSCHEDULERSTATUS2

The data type describes the current status of the cyclic transmitting list.

```
typedef struct _CANSCHEDULERSTATUS2
{
    CANLINESTATUS2 sLineStatus;
    UINT8 bTaskStat;
    UINT8 abMsgStat[16];
} CANSCHEDULERSTATUS2, *PCANSCHEDULERSTATUS2;
```

Member	Dir.	Description
<i>sLineStatus</i>	[out]	Current state of CAN controller. For further information see data structure CANLINESTATUS2 .
<i>bTaskStat</i>	[out]	Current status of transmitting task CAN_CXTTSK_STAT_STOPPED Transmitting task is stopped resp. deactivated. CAN_CXTTSK_STAT_RUNNING Transmitting task is performed resp. is active.
<i>abMsgStat</i>		Table with status of all 16 transmitting objects. Each table entry can take one of the following values: CAN_CTXMSG_STAT_EMPTY The entry is not assigned to a transmitting object resp. the entry is currently not used. CAN_CTXMSG_STAT_BUSY Transmitting object is currently processed. CAN_CTXMSG_STAT_DONE Processing of transmitting object is finished.

8.3.14 CANMSGINFO

The data type summarizes different information about CAN messages in a union. The individual values can either be addresses via byte fields or via bus bit fields.

```
typedef union _CANMSGINFO
{
    struct
    {
        UINT8 bType;
        union
        {
            UINT8 bReserved;
            UINT8 bFlags2;
        };
        UINT8 bFlags;
        UINT8 bAccept;
    } Bytes;

    struct
    {
        UINT32 type: 8;

        UINT32 ssm : 1;
        UINT32 hpm : 1;
        UINT32 edl : 1;
        UINT32 fdr : 1;
        UINT32 esi : 1;
        UINT32 res : 3;

        UINT32 dlc : 4;
        UINT32 ovr : 1;
        UINT32 srr : 1;
        UINT32 rtr : 1;
        UINT32 ext : 1;

        UINT32 afc : 8;
    } Bits;
} CANMSGINFO, *PCANMSGINFO;
```

The information are accessed byte by byte via the following byte fields:

Fields	Dir.	Description
<i>Bytes.bType</i>	[in/out]	Type of message. See <i>bits.type</i> .
<i>Bytes.bReserved</i>		Reserved. Due to compatibility reasons set field always to 0. See <i>bits.res</i> .
<i>Bytes.bFlags2</i>	[in/out]	Extended message flags. Meaning of the field is described in description of the respective bit fields <i>Bits.ssm</i> , <i>Bits.hpm</i> , <i>Bits.edl</i> , <i>Bits.fdr</i> , <i>Bits.esi</i> and <i>Bits.res</i> .
<i>Bytes.bFlags2</i>	[in/out]	Standard message flags. Meaning of the field is described in description of the respective bit fields <i>Bits.dlc</i> , <i>Bits.ovr</i> , <i>Bits.srr</i> , <i>Bits.rtr</i> and <i>Bits.ext</i> .
<i>Bytes.bAccept</i>	[out]	Shows in receive messages which filter has accepted the message. See <i>bits.afc</i> .

The information are accessed byte by byte via the following bit fields:

Bit field	Dir.	Description																																												
<i>Bits.type</i>	[in/out]	<p>Type of message. For the receiving messages the following types are defined:</p> <table> <tr> <td>CAN_MSGTYPE_DATA</td><td>Standard data message. In receive messages the field <i>dwMsgId</i> contains the ID of the message and the field <i>dwTime</i> the receiving time in ticks. The field <i>abData</i> contains depending on the length (see <i>bits.dlc</i>) the data bytes of the message. In transmit messages the field <i>dwMsgId</i> contains the message ID and the fields <i>abData</i> the data bytes to be transmitted. The field <i>dwTime</i> is set to 0. If the message is to be transmitted delayed to the message transmitted before specify desired delay time in ticks. See Transmitting Messages Delayed, p. 30.</td></tr> <tr> <td>CAN_MSGTYPE_INFO</td><td>Information message. This message type is generated by certain events resp. state changes of the control unit and registered in the receiving buffers of all active message channels. The field <i>dwMsgId</i> of the message always contains the value <i>CAN_MSGID_INFO</i>. Additionally the field <i>abData[0]</i> contains one of the following values:</td></tr> <tr> <td></td><td> <table> <thead> <tr> <th>Constant</th><th>Meaning</th></tr> </thead> <tbody> <tr> <td>CAN_INFO_START</td><td>Controller is started. Field <i>dwTime</i> contains the starting point.</td></tr> <tr> <td>CAN_INFO_STOP</td><td>Controller is stopped. Field <i>dwTime</i> contains value 0.</td></tr> <tr> <td>CAN_INFO_RESET</td><td>Controller is reset. Field <i>dwTime</i> contains value 0.</td></tr> </tbody> </table> </td></tr> <tr> <td>CAN_MSGTYPE_ERROR</td><td>Error message. This message type is generated if a bus error occurs and is registered in the receiving buffers off all active message channels, provided that the flag <i>CAN_OPMODE_ERRFRAME</i> is set during the initialization of the CAN controller. The field <i>dwMsgId</i> of the message contains the value <i>CAN_MSGID_ERROR</i>. 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The time of the event is noted in field <i>dwTime</i>. Additionally the field <i>abData[0]</i> contains the low byte of the current CAN state. See description of field <i>dwStatus</i> of structure <i>CANCAPABILITIES</i> or <i>CANCAPABILITIES2</i>. The content of all other data fields is undefined.</td></tr> <tr> <td>CAN_MSGTYPE_WAKEUP</td><td>This message type is not used resp. reserved for future expansions.</td></tr> <tr> <td>CAN_MSGTYPE_TIMEOVR</td><td>Messages of this type are generated by the time stamp counter with every overflow and registered in the receiving buffer of all active message channels. The field <i>dwTime</i> of the message contains the time of the event and the field <i>dwMsgId</i> the number of occurred overflows (normally 1). The content of the data fields <i>abData</i> is undefined.</td></tr> <tr> <td>CAN_MSGTYPE_TIMERST</td><td>This message type is not used resp. reserved for future expansions.</td></tr> </table>	CAN_MSGTYPE_DATA	Standard data message. In receive messages the field <i>dwMsgId</i> contains the ID of the message and the field <i>dwTime</i> the receiving time in ticks. The field <i>abData</i> contains depending on the length (see <i>bits.dlc</i>) the data bytes of the message. In transmit messages the field <i>dwMsgId</i> contains the message ID and the fields <i>abData</i> the data bytes to be transmitted. The field <i>dwTime</i> is set to 0. If the message is to be transmitted delayed to the message transmitted before specify desired delay time in ticks. See Transmitting Messages Delayed, p. 30 .	CAN_MSGTYPE_INFO	Information message. This message type is generated by certain events resp. state changes of the control unit and registered in the receiving buffers of all active message channels. The field <i>dwMsgId</i> of the message always contains the value <i>CAN_MSGID_INFO</i> . 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This message type is generated if a bus error occurs and is registered in the receiving buffers off all active message channels, provided that the flag <i>CAN_OPMODE_ERRFRAME</i> is set during the initialization of the CAN controller. The field <i>dwMsgId</i> of the message contains the value <i>CAN_MSGID_ERROR</i> . The time of the event is noted in field <i>dwTime</i> . 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This message type is generated by state changes of the CAN controller and registered in the receiving buffers of all active message channels. The field <i>dwMsgId</i> contains the value <i>CAN_MSGID_STATUS</i> . The time of the event is noted in field <i>dwTime</i> . Additionally the field <i>abData[0]</i> contains the low byte of the current CAN state. See description of field <i>dwStatus</i> of structure <i>CANCAPABILITIES</i> or <i>CANCAPABILITIES2</i> . The content of all other data fields is undefined.	CAN_MSGTYPE_WAKEUP	This message type is not used resp. reserved for future expansions.	CAN_MSGTYPE_TIMEOVR	Messages of this type are generated by the time stamp counter with every overflow and registered in the receiving buffer of all active message channels. The field <i>dwTime</i> of the message contains the time of the event and the field <i>dwMsgId</i> the number of occurred overflows (normally 1). The content of the data fields <i>abData</i> is undefined.	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CAN_INFO_RESET	Controller is reset. Field <i>dwTime</i> contains value 0.																																													
CAN_MSGTYPE_ERROR	Error message. This message type is generated if a bus error occurs and is registered in the receiving buffers off all active message channels, provided that the flag <i>CAN_OPMODE_ERRFRAME</i> is set during the initialization of the CAN controller. The field <i>dwMsgId</i> of the message contains the value <i>CAN_MSGID_ERROR</i> . The time of the event is noted in field <i>dwTime</i> . The field <i>abData[0]</i> contains one of the following values:																																													
	<table> <thead> <tr> <th>Constant</th><th>Meaning</th></tr> </thead> <tbody> <tr> <td>CAN_ERROR_STUFF</td><td>Stuff error</td></tr> <tr> <td>CAN_ERROR_FORM</td><td>Format error</td></tr> <tr> <td>CAN_ERROR_ACK</td><td>Acknowledge error</td></tr> <tr> <td>CAN_ERROR_BIT</td><td>Bit error</td></tr> <tr> <td>CAN_ERROR_FDB</td><td>Fast data bit error</td></tr> <tr> <td>(CANFD) CAN_ERROR_CRC</td><td>CRC error</td></tr> <tr> <td>CAN_ERROR_DLC</td><td>Faulty data length</td></tr> <tr> <td>CAN_ERROR_OTHER</td><td>Another, not specified error</td></tr> </tbody> </table>	Constant	Meaning	CAN_ERROR_STUFF	Stuff error	CAN_ERROR_FORM	Format error	CAN_ERROR_ACK	Acknowledge error	CAN_ERROR_BIT	Bit error	CAN_ERROR_FDB	Fast data bit error	(CANFD) CAN_ERROR_CRC	CRC error	CAN_ERROR_DLC	Faulty data length	CAN_ERROR_OTHER	Another, not specified error																											
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(CANFD) CAN_ERROR_CRC	CRC error																																													
CAN_ERROR_DLC	Faulty data length																																													
CAN_ERROR_OTHER	Another, not specified error																																													
CAN_MSGTYPE_STATUS	Status message. This message type is generated by state changes of the CAN controller and registered in the receiving buffers of all active message channels. The field <i>dwMsgId</i> contains the value <i>CAN_MSGID_STATUS</i> . The time of the event is noted in field <i>dwTime</i> . Additionally the field <i>abData[0]</i> contains the low byte of the current CAN state. See description of field <i>dwStatus</i> of structure <i>CANCAPABILITIES</i> or <i>CANCAPABILITIES2</i> . The content of all other data fields is undefined.																																													
CAN_MSGTYPE_WAKEUP	This message type is not used resp. reserved for future expansions.																																													
CAN_MSGTYPE_TIMEOVR	Messages of this type are generated by the time stamp counter with every overflow and registered in the receiving buffer of all active message channels. The field <i>dwTime</i> of the message contains the time of the event and the field <i>dwMsgId</i> the number of occurred overflows (normally 1). The content of the data fields <i>abData</i> is undefined.																																													
CAN_MSGTYPE_TIMERST	This message type is not used resp. reserved for future expansions.																																													

Bit field	Dir.	Description																		
		For transmitting messages exclusively the message type CAN_MSGTYPE_DATA is defined, other values are not valid.																		
<i>Bits.ssm</i>	[in]	Single shot message. If this bit is set in transmitting messages the controller tries to transmit the message only once. If the message loses its arbitration during the first transmitting attempt, the controller rejects the message and no further automatic transmitting attempt follows. If this bit is 0 no transmitting is attempted until the message has been transmitted over the bus. Regarding receiving messages this bit has no significance.																		
<i>Bits.hpm</i>	[in]	High priority message. Transmitting messages with high priority are assigned to a transmitting buffer by the controller, the transmitting buffer is prior to messages in the normal transmitting buffer. Messages of high priority are transmitted with priority to the bus. Regarding receiving messages this bit has no significance.																		
<i>Bits.edl</i>	[in/out]	Message with extended data field. For further information see description of data length field <i>Bits.dlc</i> . The bit is exclusively valid with extended controller operating mode CAN_EXMODE_EXTDATA.																		
<i>Bits.fdr</i>	[in/out]	This bit can be set in transmitting messages to transfer the data bytes and bis from the DLC field with high bit rate on the bus. If this bit is set the RTR bit is ignored. See description of <i>bits.rtr</i> . The bit is exclusively valid with extended controller operating mode CAN_EXMODE_FASTDATA.																		
<i>Bits.esi</i>	[out]	Error state indicator. Nodes that are <i>error active</i> transmit this bit dominant (0), nodes that are <i>error passive recessive</i> (1). This bit is exclusively considered in receiving messages. In transmitting messages it is has no significance and must be set to 0.																		
<i>Bits.res</i>		Reserved for further extensions. Due to compatibility reasons set field always to 0.																		
<i>Bits.dlc</i>	[in/out]	Data length code. The value defines the number of valid data bytes in field <i>abData</i> of a message. The following assignment applies:																		
		<table> <thead> <tr> <th>dlc</th> <th>Number of data bytes</th> </tr> </thead> <tbody> <tr> <td>0...8</td> <td>0...8</td> </tr> <tr> <td>9</td> <td>12</td> </tr> <tr> <td>10</td> <td>16</td> </tr> <tr> <td>11</td> <td>20</td> </tr> <tr> <td>12</td> <td>24</td> </tr> <tr> <td>13</td> <td>32</td> </tr> <tr> <td>14</td> <td>48</td> </tr> <tr> <td>15</td> <td>64</td> </tr> </tbody> </table> <p>A value higher than 8 is exclusively allowed in messages with extended data field (see CANMSG2). To transmit a message with more than 8 byte the CAN must be used in the operating mode CAN_EXMODE_EXTDATA and additionally the bit <i>edl</i> of the message to be transmitted must be set to 1. Basically this is exclusively possible with controllers with extended functionality (CAN FD).</p>	dlc	Number of data bytes	0...8	0...8	9	12	10	16	11	20	12	24	13	32	14	48	15	64
dlc	Number of data bytes																			
0...8	0...8																			
9	12																			
10	16																			
11	20																			
12	24																			
13	32																			
14	48																			
15	64																			
<i>Bits.ovr</i>	[out]	Data overrun. The bit is set to 1 in receiving messages if an overflow of the receiving FIFO took place.																		
<i>Bits.srr</i>	[in/out]	Self reception request. If the bit is set in transmitting messages the message is assigned to the receiving FIFO as soon as it was transmitted to the bus. In receiving messages a set bit indicates that it is a self reception message. This bit must not be mistaken as substitute remote request (SRR) bit of CAN FD.																		
<i>Bits.rtr</i>	[in/out]	Remote transmission request. This bit is set in transmitting messages to scan other bus participants specifically for certain messages. Observe that the bit is ignored if one of the bits <i>edl</i> or <i>fdr</i> is also set. RTR messages are not possible with CAN FD.																		
<i>Bits.ext</i>	[in/out]	Messages with extended 29 bit ID																		
<i>Bits.afc</i>	[out]	Acceptance filter code. In receiving messages this field determines the filter that lets pass the message. The following values are defined:																		
		<table> <tbody> <tr> <td>CAN_ACCEPT_ALWAYS</td> <td>The message is always accepted. All other messages than these of type CAN_MSGTYPE_DATA contain this value.</td> </tr> <tr> <td>CAN_ACCEPT_FILTER1 resp. CAN_ACCEPT_FILTER2</td> <td>The message has either been accepted by the acceptance filter (CAN_ACCEPT_FILTER1) or by the filter list (CAN_ACCEPT_FILTER2). Exclusively messages of type CAN_MSGTYPE_DATA contain this value. The filter must be used in operating mode CAN_FILTER_INCL.</td> </tr> <tr> <td>CAN_ACCEPT_EXCL</td> <td>This value is used in the filter operating mode CAN_FILTER_EXCL if a message of type CAN_MSGTYPE_DATA has been accepted. Detailed information about functionality of message filters and the different operating modes see Message Filter, p. 42.</td> </tr> </tbody> </table>	CAN_ACCEPT_ALWAYS	The message is always accepted. All other messages than these of type CAN_MSGTYPE_DATA contain this value.	CAN_ACCEPT_FILTER1 resp. CAN_ACCEPT_FILTER2	The message has either been accepted by the acceptance filter (CAN_ACCEPT_FILTER1) or by the filter list (CAN_ACCEPT_FILTER2). Exclusively messages of type CAN_MSGTYPE_DATA contain this value. The filter must be used in operating mode CAN_FILTER_INCL.	CAN_ACCEPT_EXCL	This value is used in the filter operating mode CAN_FILTER_EXCL if a message of type CAN_MSGTYPE_DATA has been accepted. Detailed information about functionality of message filters and the different operating modes see Message Filter, p. 42 .												
CAN_ACCEPT_ALWAYS	The message is always accepted. All other messages than these of type CAN_MSGTYPE_DATA contain this value.																			
CAN_ACCEPT_FILTER1 resp. CAN_ACCEPT_FILTER2	The message has either been accepted by the acceptance filter (CAN_ACCEPT_FILTER1) or by the filter list (CAN_ACCEPT_FILTER2). Exclusively messages of type CAN_MSGTYPE_DATA contain this value. The filter must be used in operating mode CAN_FILTER_INCL.																			
CAN_ACCEPT_EXCL	This value is used in the filter operating mode CAN_FILTER_EXCL if a message of type CAN_MSGTYPE_DATA has been accepted. Detailed information about functionality of message filters and the different operating modes see Message Filter, p. 42 .																			

8.3.15 CANMSG

The data type describes the structure of CAN message telegrams.

```
typedef struct _CANMSG
{
    UINT32 dwTime;
    UINT32 dwMsgId;
    CANMSGINFO uMsgInfo;
    UINT8 abData[8];
} CANMSG, *PCANMSG;
```

Member	Dir.	Description
<i>dwTime</i>		In receiving messages this field contains the starting point of the message in ticks. For further information see Reception Time of a Message, p. 28 . In transmitting messages this field determines with how many ticks delay the message is transmitted after the message sent before.
<i>dwMsgId</i>		CAN ID of the message in Intel format (aligned right) without RTR bit.
<i>uMsgInfo</i>		Bit field with information about the message type. For detailed description of bit field see CANMSGINFO .
<i>abData</i>		Array for up to 8 data bytes. Number of valid data bytes is defined by field <i>uMsgInfo.Bits.dlc</i> .

8.3.16 CANMSG2

The data type describes the structure of extended CAN message telegrams.

```
typedef struct _CANMSG2
{
    UINT32 dwTime;
    UINT32 dwMsgId;
    CANMSGINFO uMsgInfo;
    UINT8 abData[64];
} CANMSG2, *PCANMSG2;
```

Member	Dir.	Description
<i>dwTime</i>		In receiving messages this field contains the receiving point of the message in ticks. For further information see Reception Time of a Message, p. 28 . In transmitting messages this field determines with how many ticks delay the message is transmitted after the message sent before.
<i>dwMsgId</i>		CAN ID of the message in Intel format (aligned right) without RTR bit.
<i>uMsgInfo</i>		Bit field with information about the message type. For detailed description of bit field see CANMSGINFO .
<i>abData</i>		Array for up to 64 data bytes. Number of valid data bytes is defined by field <i>uMsgInfo.Bits.dlc</i> .

8.3.17 CANCYCLICTXMSG

This data type describes the structure of a cyclic transmitting list.

```
typedef struct _CANCYCLICTXMSG
{
    UINT16 wCycleTime;
    UINT8 bIncrMode;
    UINT8 bByteIndex;
    UINT32 dwMsgId;
    CANMSGINFO uMsgInfo;
    UINT8 abData[8];
} CANCYCLICTXMSG, *PCANCYCLICTXMSG;
```

Member	Dir.	Description
<i>wCycleTime</i>		Cycle time of the message in number ticks. The cycle time can be calculated in the fields <i>dwClockFreq</i> and <i>dwCmsDivisor</i> of structure CANCAPABILITIES with the following formula. $T_{cycle} [s] = (dwCmsDivisor / dwClockFreq) * wCycleTime$ The maximum value for the field is limited to the value in field <i>dwCmsMaxTicks</i> of structure CANCAPABILITIES .
<i>bIncrMode</i>		This field determines if a part of the cyclic transmitting list is automatically incremented after each transmitting. CAN_CTXMSG_INC_NO The message field is not incremented automatically. CAN_CTXMSG_INC_ID Increments the field <i>dwMsgId</i> by 1 after every transmission. If the field reaches the value 2048 (11 bit ID) resp. 536.870.912 (29 bit ID) an overflow automatically takes place. CAN_CTXMSG_INC_8 Increments an 8 bit value in the data field <i>abData</i> of the message. The data byte to be incremented is determined via the parameter <i>bByteIndex</i> . If the maximum value 255 is exceeded an overflow to 0 takes place. CAN_CTXMSG_INC_16 Increments a 16 bit value in the data field <i>abData</i> of the message. The low byte of the 16 bit value to be incremented is determined via the field <i>bByteIndex</i> . The high byte is in the data field on position <i>bByteIndex+1</i> . If the maximum value 655350 is exceeded an overflow to 0 takes place.
<i>bByteIndex</i>		Field determines the byte resp. the low byte (LSB) of the 16 bit value in data field <i>abData</i> , that is automatically incremented after each transmission. The value range of the field is limited by the data length specified in the field <i>uMsgInfo.Bits.dlc</i> of structure CANMSGINFO and it is limited to the range 0 to (<i>dlc</i> -1) in case of 8 bit increment and 0 to (<i>dlc</i> -2) in case of 16 bit increment.
<i>dwMsgId</i>		CAN ID of the message in Intel format (aligned right) without RTR bit.
<i>uMsgInfo</i>		Bit field with information about the message type. For description of bit field see CANMSGINFO .
<i>abData</i>		Array for up to 8 data bytes. Number of valid data bytes is defined by field <i>uMsgInfo.Bits.dlc</i> .

8.3.18 CANCYCLICTXMSG2

This data type describes the structure of an extended cyclic transmitting list.

```
typedef struct _CANCYCLICTXMSG2
{
    UINT16 wCycleTime;
    UINT8 bIncrMode;
    UINT8 bByteIndex;
    UINT32 dwMsgId;
    CANMSGINFO uMsgInfo;
    UINT8 abData[64];
} CANCYCLICTXMSG2, *PCANCYCLICTXMSG2;
```

Member	Dir.	Description
<i>wCycleTime</i>		Cycle time of the message in number ticks. The cycle time can be calculated in the fields <i>dwClockFreq</i> and <i>dwCmsDivisor</i> of structure CANCAPABILITIES2 with the following formula. $T_{cycle} [s] = (dwCmsDivisor / dwClockFreq) * wCycleTime$ The maximum value for the field is limited to the value in field <i>dwCmsMaxTicks</i> of structure CANCAPABILITIES2 .
<i>bIncrMode</i>		This field determines if a part of the cyclic transmitting list is automatically incremented after each transmitting. CAN_CTXMSG_INC_NO The message field is not incremented automatically. CAN_CTXMSG_INC_ID Increments the field <i>dwMsgId</i> by 1 after every transmission. If the field reaches the value 2048 (11 bit ID) resp. 536.870.912 (29 bit ID) an overflow automatically takes place. CAN_CTXMSG_INC_8 Increments an 8 bit value in the data field <i>abData</i> of the message. The data byte to be incremented is determined via the parameter <i>bByteIndex</i> . If the maximum value 255 is exceeded an overflow to 0 takes place. CAN_CTXMSG_INC_16 Increments a 16 bit value in the data field <i>abData</i> of the message. The low byte of the 16 bit value to be incremented is determined via the field <i>bByteIndex</i> . The high byte is in the data field on position <i>bByteIndex+1</i> . If the maximum value 655350 is exceeded an overflow to 0 takes place.
<i>bByteIndex</i>		Field determines the byte resp. the low byte (LSB) of the 16 bit value in data field <i>abData</i> , that is automatically incremented after each transmission. The value range of the field is limited by the data length specified in the field <i>uMsgInfo.Bits.dlc</i> of structure CANMSGINFO and it is limited to the range 0 to (<i>dlc</i> -1) in case of 8 bit increment and 0 to (<i>dlc</i> -2) in case of 16 bit increment.
<i>dwMsgId</i>		CAN ID of the message in Intel format (aligned right) without RTR bit.
<i>uMsgInfo</i>		Bit field with information about the message type. For description of bit field see CANMSGINFO .
<i>abData</i>		Array for up to 64 data bytes. Number of valid data bytes is defined by field <i>uMsgInfo.Bits.dlc</i> .

8.4 LIN Specific Data Types

The declaration of all LIN specific data types and constants is stored in the files *lintype.h*.

8.4.1 LINCAPABILITIES

The data type describes the features of a LIN connection.

```
typedef struct _LINCAPABILITIES
{
    UINT16 dwFeatures;
    UINT32 dwClockFreq;
    UINT32 dwTscDivisor;
} LINCAPABILITIES, *PLINCAPABILITIES;
```

Member	Dir.	Description												
<i>dwFeatures</i>	[out]	<p>Supported features. Value is a logical combination of one or more of the following constants:</p> <table> <tr> <td>LIN_FEATURE_MASTER</td><td>LIN controller supports the operating mode <i>Master</i>.</td></tr> <tr> <td>LIN_FEATURE_AUTORATE</td><td>LIN controller supports the automatic detection of the bit rate.</td></tr> <tr> <td>LIN_FEATURE_ERRFRAME</td><td>LIN controller returns error messages.</td></tr> <tr> <td>LIN_FEATURE_BUSLOAD</td><td>LIN controller supports calculation of the bus load.</td></tr> <tr> <td>LIN_FEATURE_SLEEP</td><td>LIN controller supports SLEEP messages (exclusively Master).</td></tr> <tr> <td>LIN_FEATURE_WAKEUP</td><td>LIN controller supports WAKEUP messages.</td></tr> </table>	LIN_FEATURE_MASTER	LIN controller supports the operating mode <i>Master</i> .	LIN_FEATURE_AUTORATE	LIN controller supports the automatic detection of the bit rate.	LIN_FEATURE_ERRFRAME	LIN controller returns error messages.	LIN_FEATURE_BUSLOAD	LIN controller supports calculation of the bus load.	LIN_FEATURE_SLEEP	LIN controller supports SLEEP messages (exclusively Master).	LIN_FEATURE_WAKEUP	LIN controller supports WAKEUP messages.
LIN_FEATURE_MASTER	LIN controller supports the operating mode <i>Master</i> .													
LIN_FEATURE_AUTORATE	LIN controller supports the automatic detection of the bit rate.													
LIN_FEATURE_ERRFRAME	LIN controller returns error messages.													
LIN_FEATURE_BUSLOAD	LIN controller supports calculation of the bus load.													
LIN_FEATURE_SLEEP	LIN controller supports SLEEP messages (exclusively Master).													
LIN_FEATURE_WAKEUP	LIN controller supports WAKEUP messages.													
<i>dwClockFreq</i>	[out]	Frequency in hertz of the primary timer												
<i>dwTscDivisor</i>	[out]	Divisor for the time stamp counter. The time stamp counter returns the time stamp for LIN messages. Frequency of time stamp counter is calculated by the frequency of the primary timer divided by the value specified here.												

8.4.2 LININITLINE

The structure is used to initialize a LIN controller and determines the operating mode and the transmission rate.

```
typedef struct _LININITLINE
{
    UINT8 bOpMode;
    UINT8 bReserved;
    UINT16 wBitrate;
} LININITLINE, *PLININITLINE;
```

Member	Dir.	Description						
<i>bOpMode</i>	[in]	<p>Operating mode of LIN controller. For the operating mode a logical combination of one or more of the following constants can be specified:</p> <table> <tr> <td>LIN_OPMODE_SLAVE</td><td>Slave mode. By default the operating mode is always active.</td></tr> <tr> <td>LIN_OPMODE_MASTER</td><td>Activate master mode (if supported see LINCAPABILITIES).</td></tr> <tr> <td>LIN_OPMODE_ERRORS</td><td>Errors are reported to the application via special LIN messages.</td></tr> </table>	LIN_OPMODE_SLAVE	Slave mode. By default the operating mode is always active.	LIN_OPMODE_MASTER	Activate master mode (if supported see LINCAPABILITIES).	LIN_OPMODE_ERRORS	Errors are reported to the application via special LIN messages.
LIN_OPMODE_SLAVE	Slave mode. By default the operating mode is always active.							
LIN_OPMODE_MASTER	Activate master mode (if supported see LINCAPABILITIES).							
LIN_OPMODE_ERRORS	Errors are reported to the application via special LIN messages.							
<i>bReserved</i>	[in]	Reserved. Value must be initialized with 0.						
<i>wBitrate</i>	[in]	Transmitting rate in bits per second. The specified value must be in between the limits that are determined by the constants LIN_BITRATE_MIN and LIN_BITRATE_MAX. If the controller is used as slave and supports an automatic bit detection the bit rate can be determined automatically by setting the value LIN_BITRATE_AUTO.						

8.4.3 LINLINESTATUS

The data type describes the current status of the LIN message.

```
typedef struct _LINLINESTATUS
{
    UINT8 bOpMode;
    UINT8 bReserved;
    UINT16 wBitrate;
    UINT32 dwStatus;
} LINLINESTATUS, *PLINLINESTATUS;
```

Member	Dir.	Description
<i>bOpMode</i>	[in]	Current operating mode of controller. Value is a logical combination of one or more in <i>lintype.h</i> defined constants <i>LIN_OPMODE</i> and corresponds to the values specified in <i>ILinControl::InitLine</i> .
<i>bReserved</i>	[out]	Not used
<i>wBitrate</i>	[out]	Currently specified transmission rate in bits per second
<i>dwStatus</i>	[out]	Current status of LIN controller. Value is a logical combination of one or more of the following constants: LIN_STATUS_TXPEND Controller is currently transmitting a message to the bus. LIN_STATUS_OVERRUN Data overflow in the receiving buffer of the controller had happened. LIN_STATUS_ERRLIM Overflow of an error counter of the controller has happened. LIN_STATUS_BUSOFF Controller has shifted to state <i>BUS-OFF</i> . LIN_STATUS_ININIT Controller is in stopped state.

8.4.4 LINMONITORSTATUS

The data type describes the current status of the LIN message monitor.

```
typedef struct _LINMONITORSTATUS
{
    LINLINESTATUS sLineStatus;
    BOOL32 fActivated;
    BOOL32 fRxOverrun;
    UINT8 bRxFifoLoad;
} LINMONITORSTATUS, *PLINMONITORSTATUS;
```

Member	Dir.	Description
<i>sLineStatus</i>	[out]	Current status of LIN controller. For further information see description of the data structure <i>LINLINESTATUS</i> .
<i>fActivated</i>	[out]	Shows if message monitor is active (TRUE) or inactive (FALSE).
<i>fRxOverrun</i>	[out]	Signalizes an overflow in the receiving buffer with the value TRUE.
<i>bRxFifoLoad</i>	[out]	Current filling level of receiving FIFO in percentage

8.4.5 LINMSGINFO

The data type summarizes different information about LIN messages in a 32 bit value. The value can be assigned byte by byte or via individual bit fields.

```
typedef union _LINMSGINFO
{
    struct
    {
        UINT8 bPid;
        UINT8 bType;
        UINT8 bDlen;
        UINT8 bFlags; } Bytes;

    struct
    {
        UINT32 pid : 8;
        UINT32 type : 8;
        UINT32 dlen : 8;
        UINT32 ecs : 1;
        UINT32 sor : 1;
        UINT32 ovr : 1;
        UINT32 ido : 1;
        UINT32 res : 4;
    } Bits;

} LINMSGINFO, *PLINMSGINFO;
```

The information of a LIN message can be accessed byte by byte via the structure element *Bytes*. The following fields are defined:

Fields	Dir.	Description
<i>Bytes.bPid</i>	[in/out]	Protected identifier, see <i>bits.pid</i>
<i>Bytes.bType</i>	[in/out]	Type of message, see <i>bits.type</i> and <i>bits.ecs</i>
<i>Bytes.bDlen</i>	[in/out]	Data length, see <i>bits.dlen</i>
<i>Bytes.bFlags</i>	[in/out]	Different flags, see <i>bits.ecs</i> , <i>bits.sor</i> , <i>bits.ovr</i> and <i>bits.ido</i>

The information of a LIN message can be accessed by the bit via the structure element *Bits*. The following bit fields are defined:

Bit field	Dir.	Description
<i>Bytes.pid</i>	[in/out]	Protected identifier of the message
<i>Bits.type</i>	[in/out]	Type of message. For the receiving messages the following types are defined: LIN_MSGTYPE_DATA Standard message. All regular receiving channels are of this type. In field <i>bPid</i> is the ID of the message, in field <i>dwTime</i> the receiving time. The field <i>abData</i> contains depending on the length (see <i>bits.dlen</i>) the data bytes of the message. In the master operating mode messages of this type can also be transmitted. Therefore the ID must be specified in field <i>bPid</i> and in field <i>abData</i> depending on the length (<i>bits.dlen</i>) the data to be transmitted. The field <i>dwTime</i> is set to 0. To transmit exclusively the ID without data <i>Bits.ido</i> is set to 1. LIN_MSGTYPE_INFO Information message. This message type is assigned in the receiving buffers of all active message monitors if certain events happen or the status of the controller is changed. The field <i>bPid</i> of the message contains the value 0xFF. The field <i>abData[0]</i> contains one of the following values: Constant Meaning

Bit field	Dir.	Description																
		<p>LIN_INFO_START Controller is started. Field <i>dwTime</i> contains the relative starting point (normally 0).</p> <p>LIN_INFO_STOP Controller is stopped. Field <i>dwTime</i> contains value 0.</p> <p>LIN_INFO_RESET Controller is reset. Field <i>dwTime</i> contains value 0.</p>																
		<p>LIN_MSGTYPE_ERROR Error message. This message type is generated if a bus error occurs and is registered in the receiving buffers off all active message channels, provided that the flag CAN_OPMODE_ERRORS is set during the initialization of the controller. The field <i>bPid</i> of the message has the value 0xFF. The time of the event is noted in field <i>dwTime</i>. The field <i>abData[0]</i> contains one of the following values:</p> <table> <thead> <tr> <th>Constant</th><th>Meaning</th></tr> </thead> <tbody> <tr> <td>LIN_ERROR_BIT</td><td>Bit error</td></tr> <tr> <td>LIN_ERROR_CHKSUM</td><td>Check sum error</td></tr> <tr> <td>LIN_ERROR_PARITY</td><td>Parity error of identifier</td></tr> <tr> <td>LIN_ERROR_SLNORE</td><td>Slave does not answer.</td></tr> <tr> <td>LIN_ERROR_SYNC</td><td>Invalid synchronization field.</td></tr> <tr> <td>LIN_ERROR_NOBUS</td><td>No bus activity.</td></tr> <tr> <td>LIN_ERROR_OTHER</td><td>Another, not specified error</td></tr> </tbody> </table> <p>The field <i>abData[1]</i> of the message contains the low byte of the current status (see LINLINESTATUS.dwStatus). The content of the other data fields is undefined.</p>	Constant	Meaning	LIN_ERROR_BIT	Bit error	LIN_ERROR_CHKSUM	Check sum error	LIN_ERROR_PARITY	Parity error of identifier	LIN_ERROR_SLNORE	Slave does not answer.	LIN_ERROR_SYNC	Invalid synchronization field.	LIN_ERROR_NOBUS	No bus activity.	LIN_ERROR_OTHER	Another, not specified error
Constant	Meaning																	
LIN_ERROR_BIT	Bit error																	
LIN_ERROR_CHKSUM	Check sum error																	
LIN_ERROR_PARITY	Parity error of identifier																	
LIN_ERROR_SLNORE	Slave does not answer.																	
LIN_ERROR_SYNC	Invalid synchronization field.																	
LIN_ERROR_NOBUS	No bus activity.																	
LIN_ERROR_OTHER	Another, not specified error																	
		<p>LIN_MSGTYPE_STATUS Status message. This message type is assigned in the receiving buffers of all active message channels if the status of the controller is changed. The field <i>bPid</i> of the message contains the value 0xFF. The time of the event is noted in field <i>dwTime</i>. The field <i>abData[0]</i> contains the low byte of the current status. The content of the other data fields is undefined. (See LINLINESTATUS.dwStatus)</p>																
		<p>LIN_MSGTYPE_WAKEUP Exclusively for transmitting messages. Messages of this type generate a <i>Wake-Up</i> signal on the bus. The fields <i>dwTime</i>, <i>bPid</i> and <i>bDlen</i> have no significance.</p>																
		<p>LIN_MSGTYPE_TMOVR Counter overflow. Messages of this type are generated by LIN messages if an overflow of the 32 bit time stamp takes place. In field <i>dwTime</i> of the message the time of the event (standard 0) and in field <i>bDlen</i> the number of timer overflows. The content of the data fields <i>abData</i> is undefined, the field <i>bPid</i> has the value 0xFF.</p>																
		<p>LIN_MSGTYPE_SLEEP <i>Go-to-Sleep</i> message. The fields <i>dwTime</i>, <i>bPid</i> and <i>bDlen</i> have no significance.</p> <p>For transmitting messages exclusively LIN_MSGTYPE_DATA, LIN_MSGTYPE_SLEEP and LIN_MSGTYPE_WAKEUP are defined, other values are not allowed.</p>																
<i>Bits.dlen</i>	[in/out]	Number of valid data bytes in field <i>abData</i> of the message																
<i>Bits.ecs</i>	[in/out]	Enhanced check sum. Bit is set to 1, if it is a message with extended check sum according to LIN 2.0.																
<i>Bits.sor</i>	[out]	Sender of response. Bit is set in messages that are transmitted by the LIN controller, i. e. in messages for which the controller has an entry in the response table.																
<i>Bits.ovr</i>	[out]	Data overrun. Bit is set to 1 if the receiving FIFO is crowded after this message is assigned.																
<i>Bits.ido</i>	[in]	ID only. Bit is exclusively in messages of type LIN_MSGTYPE_DATA relevant that are directly transmitted. If the bit in transmitting messages is set to 1 exclusively the ID without data is transmitted and serves in the master operating mode to send the IDs. Regarding all other message types this bit has no significance.																
<i>Bits.res</i>	[in/out]	Reserved for further extensions. This field is 0.																

8.4.6 LINMSG

The data type describes the structure of LIN message telegrams.

```
typedef struct _LINMSG
{
    UINT32 dwTime;
    LINMSGINFO uMsgInfo;
    UINT8 abData[8];
} LINMSG, *PLINMSG;
```

Member	Dir.	Description
dwTime		In receiving messages this field contains the relative receiving point of the message in timer ticks. The resolution of timer tick can be calculated with the fields <i>dwClockFreq</i> and <i>dwTscDivisor</i> of structure LINCAPABILITIES with the following formula: $\text{Resolution[s]} = \text{dwTscDivisor} / \text{dwClockFreq}$
uMsgInfo		Bit field with information about the message. For detailed description of bit field see LINMSGINFO .
abData	[out]	Array for up to 8 data bytes. Number of valid data bytes is determined by the field <i>uMsgInfo.Bits.dlen</i> .

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